

DESCRIPTION

CONTROL DEVICE FOR MOBILE BODY

Technical Field

5 The present invention relates to the control of a floor reaction force of a mobile body, such as a legged mobile robot and a wheeled mobile body having an active suspension. More specifically, the present invention relates to a device for properly controlling a floor
10 reaction force to minimize influences of an unknown slope, projection or depression of a floor (ground surface) with which a mobile body, such as the legged mobile robot or the wheeled mobile robot having an active suspension, comes in contact. Moreover, the present invention relates
15 to a device for properly controlling a floor reaction force while estimating the configuration of a floor.

Background Art

 Japanese Unexamined Patent Application Publication
20 No. H5-305585 by the present applicant (Patent Document 1) discloses a technology of the compliance control of both legs of a two-legged mobile robot. This technology is applicable also to a robot having, for example, four legs. In this case, according to the compliance control based on
25 the technology disclosed in the publication, a virtual plane is inclined while all legs are in contact with the virtual plane, so that an undulation or tilt over a large

area of the floor can be dealt with. According to the technology of the publication, however, there have been cases where a load (floor reaction force) is not properly distributed if a floor has a local tilt, projection or depression. As a result, poor contact with a surface sometimes occurred, causing a portion (foot) to be in contact therewith to shake or to be subjected to an undue landing impact, with consequent deteriorated properties of foot contact with the ground. This further led to a danger in that a robot easily slips or spins. Further, there have been cases where control fails to properly distribute a floor reaction force moment for restoring the posture of the robot to a desired posture to the distal portion of each leg, causing the posture of the robot to shake. There have been also cases where, if a certain portion of the robot starts vibrating, then it is inconveniently difficult to attenuate the vibration. Further, there have been cases where the failure of proper distribution control of a floor reaction force to the distal end of each leg results in excessive load on some actuators.

In addition, Japanese Unexamined Patent Application Publication No. H10-277969 (Patent Document 2) and Japanese Unexamined Patent Application Publication No. 2001-322076 (Patent Document 3) by the present applicant disclose a technology for composite-compliance control and a technology for estimating the configuration of a floor.

These technologies make it possible to properly distribute a floor reaction force to the distal portion of each leg in a two-legged mobile robot and to compositively estimate the configuration of a floor, more specifically,

5 compositively and accurately estimate the inclination of the ground contact surface of each leg distal portion and the height difference between ground contact surfaces at the same time. These technologies in the publications are, in principle, applicable to a multi-legged robot, such as
10 a four-legged robot; however, no description has been given of a technology for specifically applying them.

Further, there has been known a technique for estimating the height of a floor at the time of landing by using feelers (load sensors or contact sensors) provided
15 at the distal ends of the legs of the four-legged robot. However, this technique is a sequential technique and has been incapable of dealing with a case where a floor deforms after the landing, as with a soft ground.

Especially when the main body of the robot is severely
20 vibrating, such as when the robot is moving fast, the height of a floor cannot be correctly estimated, and there has been a danger in that load is not properly distributed to each leg.

There has been also known a technique whereby the
25 compliance control of each leg of a robot is independently conducted for each leg. This technique, however, does not take into account the fact that the legs interfere with

each other through the vibration of the body of the robot.
In other words, the compliance control is individually
carried out on each leg. For this reason, the compliance
control of each leg does not act in harmony, making it
5 impossible to properly distribute a floor reaction force
to each leg.

The present invention has been made with a view of
the background described above, and it is an object
thereof to provide a device for properly controlling a
10 floor reaction force to minimize influences of an unknown
slope, projection or depression of a floor with which a
mobile body, such as a legged mobile robot or a wheeled
mobile body having an active suspension, comes in contact.
Moreover, an object of the present invention is to provide
15 a device for properly controlling a floor reaction force
while accurately estimating the configuration of a floor.

Disclosure of Invention

According to a first invention of a control device
20 for a mobile body in accordance with the present invention,
a control device for a mobile body that controls the
operation of the mobile body comprises a desired motion
determining means for determining a desired motion of the
mobile body, such as a mobile robot having three or more
25 ground contact portions connected through the intermediary
of a plurality of joints such that mutual relative heights
can be manipulated, and an actual posture inclination

detecting means for detecting or estimating the actual posture inclination of a predetermined part, such as a base body of the mobile body, the operation of the mobile body being controlled to make the motion of the mobile body follow a desired motion, and further comprises:

node operation controlling means that categorizes the ground contact portions in a tree structure manner such that all of the ground contact portions become leaf nodes, and an intermediate node exists between the leaf nodes and a root node having all the leaf nodes as descendant nodes,

determines, on each of C-th nodes, which is a node having a plurality of ground contact portions as descendant nodes, the correction amounts of desired relative heights of a plurality of ground contact portions belonging to the C-th node for each of the C-th nodes such that a posture inclination error is approximated to zero on the basis of at least the posture inclination error, which is the difference between the actual posture inclination and a desired posture inclination of the predetermined part in the desired motion, determines, on the basis of a correction amount obtained by combining the determined correction amounts of all the C-th nodes, a corrected desired motion by adding at least a first correction of the desired relative heights of the plurality of ground contact portions belonging to each C-th node to the desired motion, and operates the joints

such that the corrected desired motion that has been determined is satisfied.

In the present invention, regarding each node having child nodes, "ground contact portions belonging to the node" means, more accurately, "belonging as descendant nodes to the node." This applies not only to the first invention but applies any one of the inventions of the present application.

According to the first invention, three or more ground contact portions provided in a mobile body are sorted into a tree structure, and the correction amounts (in other words, manipulated variables) of desired relative heights of a plurality of ground contact portions belonging to the C-th node are determined for each C-th node so as to approximate a posture inclination error to zero on each of the C-th nodes having child nodes. Then, based on a correction amount obtained by combining those correction amounts of all the C-th nodes, a corrected desired motion is determined by adding a first correction of the desired relative heights of the plurality of ground contact portions belonging to each C-th node to the desired motion. Then, the joints of the mobile body are operated such that the determined corrected desired motion is satisfied. This makes it possible to adjust the relative heights of the ground contact portions so as to approximate the posture inclination error to zero while accomplishing mutual balance of the floor reaction forces

of the plurality of ground contact portions, as compared with a case where the heights of individual ground contact portions are independently (separately) adjusted. As a result, even if a floor with which a mobile body is to be
5 in contact has a locally unknown tilt, projection or depression, an influence thereof will be minimized, permitting enhanced stability of a posture of a robot to be achieved.

In the first invention described above, preferably,
10 each node in the tree structure has a set weight, and regarding a B-th, which is each node in the tree structure, if the B-th node is the leaf node, then the height of a ground contact portion, which is the leaf node, is defined as the height of the B-th node, and if the B-th node has
15 child nodes, then a weighted mean value, which uses the weight, of the heights of all child nodes of the B-th node is defined as the height of the B-th node, and

if the node operation controlling means determines the corrected desired motion for only one arbitrary node
20 among the C-th nodes by adding a first correction of the desired relative heights of the plurality of ground contact portions belonging to that one node to the desired motion, then the desired height of that one node in the corrected desired motion is preferably maintained at a
25 desired height in the desired motion (a second invention).

According to the second invention, the desired height of each C-th node takes the weighted mean value of

the desired heights of the child nodes of the C-th node
(the desired heights are determined on the basis of the
desired heights of the ground contact portions belonging
to the C-th node in the aforesaid desired motion). If the
5 corrected desired motion is determined for only one
arbitrary node among the C-th nodes by adding a first
correction of the desired relative heights of the
plurality of ground contact portions belonging to that one
node to the desired motion of the aforesaid desired gait,
10 then the first correction is added to a desired motion
such that the aforesaid weighted mean value of the child
nodes of the aforesaid one node will be the same in a
corrected desired motion and a desired motion.

As a result, for each C-th node, the desired
15 relative heights of the plurality of ground contact
portions belonging to each C-th node can be corrected
while achieving mutual balance among the floor reaction
forces of the plurality of ground contact portions
belonging to each C-th node. This eventually permits
20 further improved stability of a posture of the robot.

In a third invention of the control device for a
mobile body in accordance with the present invention, a
control device for a mobile body that controls the
operation of the mobile body is equipped with desired
25 motion determining means for determining a desired motion
of the mobile body, such as a mobile robot having three or
more ground contact portions connected through the

intermediary of a plurality of joints such that mutual relative heights can be adjusted, and actual posture inclination detecting means for detecting or estimating the actual posture inclination of a predetermined part,
5 such as the base body of the mobile body, the operation of the mobile body being controlled to make the motion of the mobile body follow a desired motion,

when the ground contact portions are sorted into a tree structure such that each of the ground contact
10 portions provides a leaf node, and an intermediate node exists between the leaf node and a root node having all leaf nodes as descendant nodes thereof, a weight is set for each node in the tree structure,

comprising a node operation controlling means that
15 determines a corrected desired motion obtained by adding at least a first correction of desired relative heights of a plurality of ground contact portions belonging to the C-th nodes to the desired motion so as to approximate a posture inclination error to zero on the basis of the
20 posture inclination error, which is the difference between at least the actual posture inclination and a desired posture inclination of the predetermined part in the desired motion, and then operates the joints such that the corrected desired motion that has been determined is
25 satisfied,

wherein, regarding a B-th node, which is each node in the tree structure, if the B-th node is the leaf node,

then the height of the ground contact portion, which is the leaf node, is defined as the height of the B-th node, and if the B-th node has a child node, then a weighted mean value, which uses the weight, of the heights of all child nodes of the B-th node, is defined as the height of the B-th node, and if the node operation controlling means determines the desired motion for only the C-th node by adding a first correction of the desired relative heights of the plurality of ground contact portions belonging to the C-th node to the desired motion, then the desired height of the C-th node in the corrected desired motion is maintained at a desired height in the desired motion.

According to the third invention, the desired height of the predetermined C-th node takes the weighted mean value of the desired heights of the child nodes of the C-th node (this is determined on the basis of the desired heights of the ground contact portions belonging to the C-th node in the desired motion). If the aforesaid corrected desired motion is determined for only the C-th node by adding a first correction of the desired relative heights of a plurality of ground contact portions belonging to the C-th node to the desired motion, then the first correction is added to a desired motion such that the aforesaid weighted mean value of the child nodes of the C-th node will be the same in a corrected desired motion and a desired motion.

As a result, according to the third invention, while

achieving mutual balance among the floor reaction forces of the plurality of ground contact portions belonging to the C-th node, the relative heights of the ground contact portions can be adjusted so as to approximate the posture inclination error to zero. Thus, as with the first invention or the second invention, even if a floor with which a mobile body is to be in contact locally has an unknown inclination, projection or depression, the influences thereof will be minimized, permitting improved stability of a posture of a robot to be achieved.

In the second invention and the third invention described above, regarding each node having child nodes in the tree structure, the weights of all child nodes of each node are preferably set such that the total sum of the weights of all the child nodes will be one (a fourth invention).

Preferably, the second invention and the third invention described above is equipped with a means for variably setting the weights of the nodes, and if the leaf nodes corresponding to ground contact portions that are not in contact with the ground are defined as D-th nodes, then the means for setting the weights sets the weight of each D-node or the weight of at least one of ancestor nodes of the D-th node to zero (a fifth invention).

The fifth invention makes it possible to prevent the height of the ground contact portion not in contact with the ground, which cannot contribute to bringing the

posture inclination error to zero, from being wastefully corrected. The fifth invention may be combined with the fourth invention.

5 In the first invention and the second invention, if the ground contact portions are connected to the base body of the mobile body in such a manner that they are movable with respect to the base body, then the node operation controlling means, when determining the corrected desired motion, preferably determines the corrected desired motion by further adding to the desired motion a correction of a
10 desired posture of the base body to restrain slippage, such as twist, of the ground contact portions belonging to the C-th node on a floor surface (a sixth invention). This applies also to the third invention described above
15 (a seventh invention).

If there are many ground contact portions connected to the base body of a mobile body, the degrees of freedom of joints of the mobile body will be excessively low, causing the corrections of the relative heights of the
20 ground contact portions to be subject to mechanical restrictions. If the joints are forcibly operated to satisfy determined desired relative heights, then some ground contact portions may incur slippage, including twist. In such a situation wherein a slippage occurs,
25 there is a danger in that the floor reaction forces of the ground contact portions become inappropriate and the stability of a posture of the robot is impaired. In such

a case, as in the sixth invention and the seventh invention, rather than simply correcting the desired relative heights of the ground contact portions belonging to the C-th node, a correction of a desired posture of the base body is further added to a desired motion so as to determine the corrected desired motion, thus making it possible to restrain slippage, including twist. Hence, the ground contact portions will not be subjected to undue floor reaction forces, making it possible to secure stability of a posture of the mobile body by setting the floor reaction forces to be appropriate.

In the sixth invention and the seventh invention, more preferably, the node operation controlling means determines the corrected desired motion such that the horizontal position of the overall center-of-gravity of the mobile body in the corrected desired motion or the horizontal position of a predetermined representative point of the base body of the mobile body is substantially the same as the horizontal position in the desired motion (an eighth invention). The eighth invention makes it possible to prevent the overall center-of-gravity of the mobile body from being considerably shifted in the horizontal direction relative to a proper position in a desired gait when a corrected desired motion is determined by adding a correction of a desired posture of the base body to a desired motion. Hence, the relative heights of the ground contact portions of the C-th node and the

posture of the base body can be corrected while maintaining proper stability of the mobile body.

5 The sixth invention is suited to a case where the mobile body is a robot equipped with a plurality of link mechanisms extended from its base body, and at least one link mechanism out of the plurality of link mechanisms has a joint provided at an intermediate portion between at least its distal portion and the end portion adjacent to the base body, the intermediate portion being the ground
10 contact portion (a ninth invention).

 The seventh invention is suited to a case where the mobile body is a robot equipped with a plurality of link mechanisms extended from its base body, and at least one link mechanism out of the plurality of link mechanisms has
15 a joint provided at an intermediate portion between at least its distal portion and the end portion adjacent to the base body, the intermediate portion being the ground contact portion belonging to the C-th node (a tenth invention).

20 More specifically, a robot with a plurality of link mechanisms extended from its base body usually contacts the ground through the distal portions of the link mechanisms; therefore, an attempt to make the robot contact the ground at intermediate portions of the link
25 mechanisms (e.g., an attempt to make a human type mobile robot contact the ground at an intermediate portion (knee) of a leg thereof) leads to the above-mentioned slippage,

such as twist, due to an insufficient degree of freedom of a joint in some cases. Hence, the sixth invention or the seventh invention is suited to a case where a mobile body is constructed as described in the ninth invention or the tenth invention.

In these ninth invention and tenth invention, the intermediate portion is preferably provided with an elastic member that resiliently deforms when it comes in contact with the ground (an eleventh invention).

With this arrangement, the capability of adjusting a floor reaction force by correcting the relative heights of the intermediate portions is enhanced, and the stability of a posture of a mobile body (robot) can be easily secured.

Further, the sixth invention is suited also to a case where the mobile body is equipped with a plurality of link mechanisms which are extended from its base body and each of which has one or more joints, and at least one link mechanism among the plurality of link mechanisms and the base body are provided with the ground contact portions (a twelfth invention).

Further, the seventh invention is suited also to a case where the mobile body is equipped with a plurality of link mechanisms which are extended from its base body and each of which has one or more joints, at least one link mechanism among the plurality of link mechanisms and the base body are provided with the ground contact portions,

and ground contact portions belonging to the C-th node include at least the ground contact portion of the base body (a thirteenth invention).

For instance, when making a robot that has one or
5 more legs (link mechanisms) extended from a base body (a body or the like) sit down, the base body is to come in contact with the ground. And in such a case, an insufficient degree of freedom of joints occasionally results, causing the aforementioned slippage, such as
10 twist, to take place. Thus, the sixth invention or the seventh invention is suited also to a case where a mobile body is constructed as described in the twelfth invention or the thirteenth invention.

In these twelfth invention and the thirteenth
15 invention, preferably, at least one ground contact portion of the base body is provided with an elastic member that resiliently deforms when it comes in contact with the ground (a fourteenth invention).

With this arrangement, the capability of adjusting a
20 floor reaction force by correcting the relative heights of the ground contact portions in the base body is enhanced, and the stability of a posture of a mobile body (robot) can be easily secured.

The sixth to the fourteenth inventions described
25 above may be combined with the second invention, the fourth invention or the fifth invention described above.

Further, the first invention and the third invention

described above (or the first to the fourteenth inventions) preferably comprises a means for determining a translational force component of a desired floor reaction force to be applied to ground contact portions belonging to the C-th node when the joint is operated to satisfy the corrected desired motion if the ground contact portions are connected to the base body through the intermediary of connecting mechanisms such that they are movable with respect to the base body of the mobile body,

wherein the node operation controlling means comprises a means for estimating a deformation amount that occurs at the connecting mechanisms between the base body and the ground contact portions belonging to the C-th node and the ground contact portions when the translational force component of the desired floor reaction force is applied to the ground contact portions belonging to the C-th node on the basis of at least the translational force components of the desired floor reaction forces of the ground contact portions belonging to the C-th node, and determines the corrected desired motion by further adding a second correction of the desired heights of the plurality of ground contact portions belonging to the C-th node, which is for canceling the estimated deformation amount, to the desired motion (a fifteenth invention).

According to the fifteenth invention, the occurrence of a deformation, such as a flexure, of the connecting mechanisms or the ground contact portions caused by a

floor reaction force applied when the ground contact portions come in contact with the ground is taken into account, and the amount of the deformation is estimated on the basis of the translational force component of a
5 desired floor reaction force. Then, the second correction of the desired heights of the ground contact portions belonging to the C-th node for canceling the estimated deformation amount is further added to the desired motion so as to determine the corrected desired motion. Thus,
10 the fifteenth invention makes it possible to apply a floor reaction force that properly approximates the posture inclination error to zero to a mobile body while compensating for the influences of the deformations of the connecting mechanisms or the ground contact portions,
15 allowing the stability of a posture of the mobile body to be further improved.

Preferably, the first invention and the third invention (or the first to the fifteenth inventions) comprises a floor configuration estimating means for
20 estimating a parameter that specifies the relative heights of the ground contact surfaces of at least a plurality of ground contact portions belonging to the C-th node as the floor configuration parameter that represents a floor configuration,

25 wherein the node operation controlling means determines the corrected desired motion by further adding a third correction of the desired relative heights of a

plurality of the ground contact portions belonging to the C-th node on the basis of an estimated value of a floor configuration parameter when determining the corrected desired motion (a sixteenth invention).

5 According to the sixteenth invention, a third correction of the desired relative heights of a plurality of the ground contact portions belonging to the C-th node on the basis of an estimated value of a floor configuration parameter that specifies at least the
10 relative heights of the ground contact surfaces of a plurality of ground contact portions belonging to the C-th node is further added to a desired motion; therefore, even if an actual floor configuration differs from the one assumed in the desired motion, it is possible to make the
15 ground contact surfaces of the ground contact portions properly come in contact with the actual floor surface when they are to be in contact with it and consequently to cause a floor reaction force that approximates the posture inclination error to zero to properly act on a mobile body.
20 Hence, the stability of a posture of the mobile body can be further enhanced.

 Preferably, the sixteenth invention comprises a floor reaction force detecting means for detecting or estimating an actual floor reaction force that acts on
25 each of the ground contact portions,

 wherein the floor configuration estimating means performs estimation while sequentially updating the floor

configuration parameter on the basis of a past value of an estimated value of the floor configuration parameter, a difference between the corrected desired motion and the desired motion, the corrected motion, at least either a
5 detected value or an estimated value of an actual joint displacement, which is a displacement amount of each joint of the mobile body, the actual posture inclination, and an actual floor reaction force of each of the ground contact portions belonging to at least the C-th node (a
10 seventeenth invention).

Alternatively, the invention preferably comprises a floor reaction force detecting means for detecting or estimating an actual floor reaction force that acts on each of the ground contact portions, and

15 a means for sequentially determining at least an actual node floor reaction force, which is an actual value of the node floor reaction force of each child node of the C-th node, from the actual floor reaction force of each ground contact portion belonging to the C-th node if,
20 regarding A-th nodes, which are the nodes in the tree structure, the A-th nodes are the leaf nodes, then the floor reaction forces acting on the ground contact portions, which are the leaf nodes, are defined as the node floor reaction forces of the A-th nodes, and if the
25 A-th nodes have child nodes, then the resultant force of the node floor reaction forces of all the child nodes of the A-th nodes is defined as the node floor reaction force

of the A-th nodes,

wherein the floor configuration estimating means performs estimation while sequentially updating the floor configuration parameter on the basis of the past value of an estimated value of the floor configuration parameter, the difference between the corrected desired motion and the desired motion, the corrected motion, at least either a detected value or an estimated value of an actual joint displacement, which is a displacement amount of each joint of the mobile body, the actual posture inclination, and a relative relationship among the actual node floor reaction forces of the child nodes of at least the C-th node (an eighteenth invention).

Alternatively, if the ground contact portions are connected to the base body through the intermediary of connecting mechanisms such that they are movable with respect to the base body of the mobile body,

the invention preferably comprises a deformation amount detecting means for detecting or estimating the amounts of deformations that occur at the connecting mechanisms between the base body and the ground contact portions and at the ground contact portions,

wherein the floor configuration estimating means performs estimation while sequentially updating the floor configuration parameter on the basis of the past value of an estimated value of the floor configuration parameter, a difference between the corrected desired motion and the

desired motion, the corrected motion, at least either a detected value or an estimated value of an actual joint displacement, which is a displacement amount of each joint of the mobile body, the actual posture inclination, and
5 the deformation amount associated with each ground contact portion belonging to at least the C-th node (a nineteenth invention).

According to the seventeenth invention, the eighteenth invention, and the nineteenth invention, floor
10 configuration parameters can be properly estimated while sequentially updating them in real time. Supplementally, in the nineteenth invention, it is not necessarily required that all the connecting mechanisms be provided with joints.

15 Further, the nineteenth invention comprises, for example, a floor reaction force detecting means for detecting or estimating an actual floor reaction force acting on each of the ground contact portions, wherein the deformation amount detecting means estimates the
20 deformation amount on the basis of the actual floor reaction force (a twentieth invention).

By detecting or estimating an actual floor reaction force as described above and using it, the deformation amounts of the connecting mechanisms or the ground contact
25 portions can be properly estimated.

In the sixteenth invention (or the sixteenth to the twentieth inventions), each node in the tree structure has

a set weight, and regarding a B-th node, which is a node in the tree structure, if the B-th node is the leaf node, then the height of the ground contact surface of the ground contact portion, which is the leaf node, is defined as the height of the ground contact surface of the B-th node, and if the B-th node has child nodes, then a weighted mean value, which uses the weight, of the heights of all child nodes of the B-th node is defined as the height of the ground contact portion of the B-th node, and when these definitions apply,

the floor configuration parameter estimated by the floor configuration estimating means is preferably a parameter that specifies a relative relationship of the heights of the ground contact surfaces of a plurality of child nodes of the C-th node (a twenty-first invention).

According to the twenty-first invention, defining the height of the ground contact surface of the B-th node having child nodes as the weighted mean value of the child nodes, as described above, makes it possible to determine a floor configuration parameter related to the configuration of a floor with which a plurality of ground contact portions belonging to the C-th node comes in contact by the relative relationship among the heights of the ground contact surfaces of the plurality of child nodes of the C-th node. Hence, floor configuration parameters can be estimated without grasping the absolute heights of the ground contact portions. This permits

easier processing for estimating a floor configuration.

In the twenty-first invention, if at least one of the child nodes of the C-th node is about to float, the floor configuration estimating means preferably estimates the floor configuration parameter that specifies the relative relationship of the heights of the ground contact surfaces of the plurality of child nodes while retaining, at a fixed value, the relative height of the ground contact surface of the child node that is about to float (a twenty-second invention).

More specifically, the state in which at least one of the child nodes of the C-th node is about to float means that the ground contact surface of the child node has left or is about to leave an actual floor surface; therefore, the height of the ground contact surface of the child node does not reflect the height of the actual floor surface. Hence, according to the twenty-second invention, in such a state, the floor configuration parameter that specifies the relative relationship of the heights of the ground contact surfaces of the plurality of child nodes is estimated while holding, at a fixed value, the relative height of the ground contact surface of the child node that is about to float. This makes it possible to prevent a floor configuration parameter from diverging into a value that does not reflect an actual floor surface configuration, and to estimate a floor configuration parameter that reflects an actual floor surface

configuration. Consequently, it is possible to prevent an inappropriate floor configuration parameter from being used to correct the relative heights of ground contact portions, which would impair the stability of a posture of a mobile body.

Further, in the sixteenth invention (or the sixteenth to the twenty-second inventions) described above, the floor configuration estimating means preferably estimates the floor configuration parameter by using a low-pass filter to alleviate fluctuation in the floor configuration parameter (a twenty-third invention). Using a low-pass filter like this makes it possible to prevent a floor configuration parameter from frequently varying due to a vibration or the like when a mobile body moves.

Further, in the sixteenth invention (or the sixteenth to the twenty-third inventions), a weight for estimating a floor configuration is set on each node of the tree structure, and

if processing in which, when a predetermined type of state amount, such as a height or a floor reaction force, is associated with each leaf node in the tree structure, the state amount of each node having child nodes is defined as a weighted mean value, which uses the weight, of the state amounts of all child nodes of the node, a value obtained by subtracting a state amount of a parent node of each node from the state amount of the node is determined as a node relative state amount of the node on

the node except a root node, and zero is determined as a relative state amount of the root node, is defined as the processing for relatively hierarchizing the predetermined type of state amount on each node,

5 if a node relative floor reaction force
 $F_{n_rel}(n=1,2,...)$ hierarchically relativized on each node
is determined on the basis of a floor reaction force
 $F_n(n=1,2,...)$ acting on each of the ground contact portions,
which are the leaf nodes, and when a vector
10 $(Fa1_rel, Fa2_rel, ..., Far_rel)$ having the node relative
floor reaction forces of all child nodes a_j ($j=1,2,...,r$. r
denotes the total number of the child nodes of an n -th
node) of an n -th node, which is an arbitrary node having
child nodes, is represented by a linear linkage of a
15 plurality of predetermined mutually independent vectors
 $R(j)$ ($j=1,2,...,r-1$) that are all orthogonal to a vector
 $(Wa1, Wa2, ..., War)$ having the weights of all child nodes of
the n -th node as its elements, a vector having a
coefficient of the linear linkage as its element is
20 defined as a node expansion floor reaction force moment
 M_{n_exp} of the n -th node, and

 if a node relative height $Z_{n_rel}(n=1,2,...)$
hierarchically relativized on each node is determined on
the basis of a height $Z_n(n=1,2,...)$ of the ground contact
25 surface of each of the ground contact portions, which are
the leaf nodes, and when a vector $(Za1_rel,$
 $Za2_rel, ..., Zar_rel)$ having the node relative heights of

all child nodes a_j ($j=1,2,\dots,r$. r denotes the total number of the child nodes of an n -th node) of the n -th node as its elements is expressed by a linear linkage of the plurality of the predetermined mutually independent
5 vectors $R(j)$ ($j=1,2,\dots,r-1$), a vector having a coefficient of the linear linkage as its element is defined as a node expansion inclination angle θ_n of the n -th node,

then, the floor configuration estimating means may estimate the floor configuration parameter by using at
10 least the node expansion floor reaction force moment $M_{n_exp}(n=C)$ or the node expansion inclination angle $\theta_n(n=C)$ of at least the C -th node (a twenty-fourth invention).

Using the node expansion floor reaction force moment
15 or the node expansion inclination angle defined as described above makes it possible to properly estimate a floor configuration parameter that represents a floor configuration even if there are four or more ground contact portions belonging to the C -th node.

20 In the twenty-fourth invention, regarding a B -th node, which is a node in the tree structure, if the B -th node is the leaf node, then the height of the ground contact surface of the ground contact portion, which is the leaf node, is defined as the height of the ground
25 contact surface of the B -th node, and if the B -th node has child nodes, then a weighted mean value, which uses the weight, of the heights of the ground contact surfaces of

all child nodes of the B-th node, is defined as the height of the ground contact surface of the B-th node, then

the floor configuration parameter preferably includes a parameter that uses the node expansion

5 inclination angle to indicate the relative height of the ground contact surface of each child node of the C-th node (a twenty-fifth invention).

With this arrangement, a floor configuration parameter can be properly estimated by using the node
10 expansion inclination angle even if there are four or more ground contact portions belonging to the C-th node.

Further, more specifically, the twenty-fourth invention comprises a floor reaction force detecting means for detecting or estimating an actual floor reaction force
15 acting on each of the ground contact portions,

wherein the node operation controlling means comprises a means for sequentially determining the node expansion moment on the basis of at least an actual floor reaction force of each of the ground contact portions, and
20 a means for sequentially determining the node expansion inclination angle by multiplying the determined node expansion moment by a predetermined matrix, and estimates a new floor configuration parameter on the basis of the determined node expansion inclination angle and the past
25 value of an estimated value of the floor configuration parameter (a twenty-fifth invention).

According to the twenty-fifth invention, the node

expansion moment is sequentially determined on the basis of at least the actual floor reaction force of each of the ground contact portions and the node expansion inclination angle is sequentially determined by multiplying the
5 determined node expansion moment by a predetermined matrix; therefore, a new floor reaction force parameter can be determined while sequentially updating it on the basis of the determined node expansion inclination angle and the past value of an estimated value of the floor
10 configuration parameter.

In the first to the twenty-fifth inventions described above, "floor reaction force" is to include a reaction force received from an object other than a floor with which a mobile body comes in contact rather than
15 simply meaning a reaction force acting on the mobile body from a floor (or the ground), as in its original meaning. Further, the ground contact portion is to include not only a portion that comes in contact with a floor (or the ground) but also a portion of the mobile body that comes
20 in contact with an object.

Brief Description of the Drawings

Fig. 1 is an overall external view of a robot in accordance with a first embodiment and a second embodiment
25 of the present invention, Fig. 2 is a block diagram showing the functional construction of a control device of the first embodiment, Figs. 3(a) to (c) and Figs. 4(a) to

(c) are diagrams for explaining an operation of the robot (four-legged robot) of the first embodiment, Figs. 5(a) to (c) are graphs showing setting examples of weights in the first embodiment, and Fig. 5(d) is a graph showing a
5 setting example of a ZMP (desired total floor reaction force central point) in the first embodiment. Fig. 6 is a diagram showing the hierarchical structure of nodes in the first embodiment, Fig. 7 is a diagram showing a relationship between desired node floor reaction force
10 central points and weights, Fig. 8 is a diagram showing a relationship between desired node floor reaction forces and weights, and Fig. 9 is a flowchart showing a main routine processing of the control device of the first embodiment. Fig. 10 to Fig. 14 are diagrams illustrating
15 desired node floor reaction force translational force components, actual node floor reaction force translational force components, actual node floor reaction force moments, compensating total floor reaction force moments, and node compensating floor reaction force moments, respectively,
20 of a robot (four-legged robot) of the first embodiment. Fig. 15 and Fig. 16 are diagrams for explaining position corrections by node compensating angles (compliance operation) in the first embodiment, Fig. 17 to Fig. 21 are block diagrams respectively showing the functional
25 constructions of a hierarchical compliance operation determiner, a compensating total floor reaction force moment distributor, a θ 1423 determiner (compensating

angle determiner), a θ 14 determiner (compensating angle determiner), and a mechanism deformation compensation amount calculator in the first embodiment, Fig. 22 is a flowchart showing the processing for determining compensating angles, and Fig. 23 is a diagram for explaining another example of a hierarchical structure related to the robot according to the first embodiment. Fig. 24 is a diagram for explaining the hierarchical structure of a robot (six-legged robot) according to a second embodiment, Fig. 25 is a block diagram showing the functional construction of a hierarchical compliance operation determiner in the second embodiment, Fig. 26 to Fig. 28 are diagrams respectively illustrating the translational force components of desired node floor reaction forces, the translational force components of actual node floor reaction forces, and actual node floor reaction force moments of the robot (six-legged robot) according to the second embodiment, Figs. 29(a) and (b) are diagrams for explaining the technique for setting a node compensating floor reaction force moment in the second embodiment, and Fig. 30 and Fig. 31 are diagrams for explaining a position correction by a node compensating angle (compliance operation) in the second embodiment. Fig. 32 and Fig. 33 are block diagrams respectively showing the functions of a θ 145236 determiner (compensating angle determiner) and a θ 145 determiner (compensating angle determiner) in the second

embodiment, and Fig. 34 is a diagram for explaining another example of a hierarchical structure related to the robot according to the second embodiment. Fig. 35 is a block diagram showing the functional construction of a hierarchical compliance operation determiner in a third embodiment, Fig. 36 is a flowchart showing a main routine processing of a control device in the third embodiment, Fig. 37 to Fig. 39 are diagrams for explaining concepts and terms in the third embodiment, Fig. 40 is a block diagram showing the function of a floor configuration estimator in the third embodiment, and Fig. 41 is a flowchart showing the processing of a floor height error estimation processing subroutine in Fig. 40. Fig. 42 and Fig. 43 are diagrams for explaining the processing for hierarchical relativization in a four-legged robot and a six-legged robot, respectively. Fig. 44 is a diagram showing examples of setting request modes of nodes related to estimating a floor configuration, and Fig. 45 to Fig. 55 are flowcharts showing the processing for estimating a floor configuration. Fig. 56 is a block diagram showing the functions of a floor configuration estimator in a fourth embodiment, and Fig. 57 is a block diagram showing the functions of a floor configuration estimator in a fifth embodiment. Fig. 58 and Fig. 59 are diagrams showing a state wherein a robot (two-legged mobile robot) in a sixth embodiment is on its knee in contact with a floor, Fig. 60 is a diagram showing the construction of a

floor reaction force sensor of a knee of the robot in the sixth embodiment, Fig. 61 is a diagram showing a hierarchical structure of nodes in the sixth embodiment, and Fig. 62 is a block diagram showing the functional construction of a hierarchical compliance operation determiner in the sixth embodiment. Figs. 63(a) to (c) are diagrams for explaining a technique for correcting the posture of the body of the robot in the sixth embodiment, Fig. 64 is a diagram for explaining a technique for correcting the position/posture of the body of the robot in the sixth embodiment, and Fig. 65 is a block diagram showing the functions of an inverse kinematics calculator in the sixth embodiment. Fig. 66 is a block diagram showing the functions of an inverse kinematics calculator in a seventh embodiment, and Fig. 67 and Fig. 68 are diagrams for explaining a technique for correcting the posture of a robot in the seventh embodiment. Fig. 69 is a diagram showing the construction of a robot in an eighth embodiment and Fig. 70 is a diagram showing a hierarchical structure of nodes in the eighth embodiment.

Best Mode for Carrying Out the Invention

First, major terms to be used in the explanation of the embodiments of the present invention will be explained.

In the technology of the composite-compliance control disclosed in Japanese Unexamined Patent Application Publication No. H10-277969 previously proposed

by the present applicant, floor reaction forces are sorted for each leg on the assumption that floor reaction forces are received at the distal portion (foot) of a leg of a robot. In comparison therewith, according to the

5 embodiments of the present description, situations are also considered in which floor reaction forces are received at portions other than the distal portions of legs, e.g., a situation in which a human type robot is on its knee, sitting on a chair, or has its arm in contact with the ground. For this reason, a portion of a legged mobile robot that comes in contact with a floor and receives a reaction force in a predetermined operation of the robot is referred to as "the ground contact portion."

10 In this case, "floor" does not simply refers to a floor (or the ground) in a conventional sense, but "floor" also includes an object with which the robot comes in contact and receives a reaction force during its movement, such as a chair (a chair on which the robot sits) fixed to the floor (or the ground). Thus, if, for example, a two-

15 legged mobile robot sits on a chair or the like, then the waist of the robot will correspond to the ground contact portion. In a normal travel of a legged mobile robot (in the walking or the like of the two-legged mobile robot), the distal portion (foot or the like) of each leg will of course correspond to the ground contact portion.

20 To categorize (discriminate) ground contact portions, even if ground contact portions are distributed such that

they are separated at a plurality of locations on the same link (a part corresponding to a single rigid body) (if a plurality of portions separated from each other on the same link is in contact with the ground), that is, even if a plurality of ground contact surfaces are not connected on the same link, these will be put together and defined as one ground contact portion. For instance, if the ground contact portion provided with four spike pins comes in contact with the ground through the intermediary of the spike pins, then the individual ground contact surfaces of the four spike pins will be put together and regarded as one ground contact portion. However, it is not always required to put the ground contact surfaces together into one.

An n-th ground contact portion is a designation for identifying the ground contact portion which has been categorized (discriminated) according to such a rule and to which an identification number n ($n=1,2,3,\dots$) has been assigned.

A ground contact portion floor reaction force refers to a floor reaction force acting on the ground contact portion, and the floor reaction force acting on an n-th ground contact portion, in particular, is referred to as the n-th ground contact portion floor reaction force. The total floor reaction force is the resultant force of the floor reaction forces acting on all ground contact portions. The floor reaction force central point is the

point of action at which the horizontal component of a moment generated by a floor reaction force at that point reaches zero.

5 A floor reaction force, such as the ground contact portion floor reaction force or a total floor reaction force, is usually expressed by a set of the point of action of a force and a translational force and moment applied to that point of action. For the same floor reaction force, there are a limitless number of sets of
10 point of action, translational force and moment for expressing the floor reaction force. Among them, there is an expression of a floor reaction force that uses, as the point of action, a point at which a moment component (the horizontal component of a moment) except a component about
15 a vertical axis (vertical component) reaches zero. The point of action in this expression is referred to as a floor reaction force central point in the present description. A floor reaction force central point may be defined as a point at which the floor surface parallel
20 component (the component parallel to a floor surface) of a moment generated by a floor reaction force at that point reaches zero.

In the present description, "floor surface" may alternatively be a virtual floor surface (a floor surface
25 assumed in a desired gait and it does not necessarily coincide with an actual floor surface) described in Japanese Unexamined Patent Application Publication No. H5-

318340 previously proposed by the present applicant.

Supplementally, the floor reaction force central point of the ground contact portion is usually set on the ground contact surface thereof (the surface in contact with a floor) if the ground contact portion is in contact with the ground. Meanwhile, the ground contact portion floor reaction force while the ground contact portion is moving in the air is always zero, so that a moment horizontal component of the ground contact portion floor reaction force will be zero at any point of action. This means that the floor reaction force central point can be arbitrarily set. However, to smoothly control the operation of a robot, a desired floor reaction force central point desirably moves in continuity. Hence, according to the embodiments in the present description, a floor reaction force central point of the ground contact portion floor reaction force is defined as the point of action that moves together with the ground contact portion when the ground contact portion moves in the air.

According to the embodiments in the present description, in the compliance control operation in which the position/posture of each ground contact portion are corrected on the basis of at least an actual floor reaction force (a floor reaction force actually acting on a robot), the compliance control operation is not simply performed on each of ground contact portions irrelevantly (independently) from each other. The embodiments in the

present description are characterized in that ground
contact portion are sorted by a tree structure and
operations for correcting the positions/postures of ground
contact portions are determined on the basis of at least
5 an actual floor reaction force acting on each group that
has been sorted (the actual floor reaction forces or the
resultant force thereof acting on all ground contact
portions included in each group). Hereinafter, sorting by
the tree structure may be referred to as
10 "hierarchization."

For the desired values of variables generated by a
gait generating device of a legged mobile robot in the
embodiments in the present description, "desired" will be
attached to the beginning of the names of variables. For
15 the values of the variables in an actual legged mobile
robot (actually detected values or estimated values,
because true values are unknown), "actual" will be
attached to the beginning of the names of variables. The
above "actual floor reaction force" is an example thereof.

20 The targets of the total floor reaction forces (the
resultant force of the actual floor reaction forces acting
on all ground contact portions of the robot) in the
compliance control (floor reaction force control) to be
discussed later will be referred to as desired total floor
25 reaction forces. The point at which the moment horizontal
component of a desired total floor reaction force reaches
zero will be referred to as a desired total floor reaction

force central point.

5 The point on a floor surface at which the moment
horizontal component of the resultant force of an inertial
force generated by a motion of a desired gait of a mobile
robot (the motion of each portion of the robot in a
desired gait) and the gravity acting on the robot becomes
zero will be referred to as a desired ZMP. The motion of
a desired gait is determined by the time series of the
desired position/posture of each portion of the robot in
10 the desired gait, so that the time series of the desired
position/posture of the portion will be generically
referred to as a motion or a desired motion of a desired
gait. Supplementally, if these time series can be
specified, then desired motions may be described by
15 expressions that are different from the desired motions
defined as described above. For example, a set of the
time series of the desired displacements of joints of a
robot and the time series of the desired position/posture
of a particular portion, such as a base body, may be used
20 as a desired motion.

 A desired total floor reaction force is usually a
total floor reaction force that dynamically balances with
the motion patten of a desired gait (the time-series
pattern of a desired motion). Hence, a desired total
25 floor reaction force central point usually agrees with a
desired ZMP. Thus, in the following explanation, a
desired total floor reaction force central point and a

desired ZMP will be used without discriminating them in many cases. Exceptionally, however, in the case of controlling a robot explained in, for example, Patent No. 3269852 previously proposed by the present applicant, a
5 desired total floor reaction force central point and a desired ZMP do not necessarily agree with each other. In the following explanation, the term, desired ZMP, will be used in some cases, but there will be some places where the term, desired total floor reaction force central point,
10 should be used to be precise.

It may be assumed that, in a desired gait of a mobile robot, the robot is subject to a reaction force (an external force) other than a floor reaction force from an environment. And, the reaction force (the external force)
15 other than a floor reaction force may be referred to as, for example, a desired object reaction force, and the definition of a desired ZMP described above may be expanded as follows. The resultant force of the inertial force generated by a motion pattern of a desired gait of a
20 robot, the gravity acting on the robot, and a desired object reaction force may be dynamically determined, and if the moment generated at a certain point on a floor surface by the resultant force is zero except for a component about a vertical axis, then the point may be
25 defined anew as a desired ZMP. However, if a desired object reaction force is taken as one form of a floor reaction force, then the definition of a desired ZMP may

be the same definition previously described.

Based on the above, the embodiments of the present invention will be explained in detail below.

5 [First Embodiment]

Fig. 1 is an external view of a general multi-legged mobile robot (legged mobile robot) according to first and second embodiments. Fig. 1 shows that the robot 1 has six legs (leg bodies), namely, a first leg #1 to a sixth leg
10 #6; however, it does not have the fifth leg #5 and the sixth leg #6 in the first embodiment. This means that, in the first embodiment, the robot 1 is a four-legged robot having four legs (leg bodies), the first leg #1 to the fourth leg #4. In Fig. 1, the components of the robot 1
15 according to the second embodiment are shown by parenthesized reference numerals.

As shown in Fig. 1, in the robot 1 (the four-legged robot) according to the first embodiment, two legs (the first leg #1 and the third leg #3) are extended from the
20 right side of a body 24, which is the base body of the robot 1, such that they are arranged side by side in the longitudinal direction, and in the same manner, two legs (the second leg #2 and the fourth leg #4) are extended from the left side of the body 24 such that they are
25 arranged side by side in the longitudinal direction. A discoid ground contact portion 10 is attached to the distal portion of each of the legs #1 to #4 through the

intermediary of a spherical joint 12, which is a free joint. Hereinafter, when the ground contact portions 10 need to be discriminated among the legs #1 to #4, they will be referred to as the first ground contact portion, the second ground contact portion, the third ground contact portion, and the fourth ground contact portion.

Each ground contact portion 10 is engaged with the spherical joint 12 such that its central point agrees with the central point of the spherical joint 12 and that a floor reaction force moment (the moment component of a floor reaction force) will not act on the central point of the ground contact portion 10 (strictly speaking, the spherical joint 12). This means that the floor reaction force moment (actual floor reaction force moment) at the central point of the ground contact portion 10 will be always zero.

In the robot 1 shown in the figure, each of the legs #1 to #4 is provided with joints 14 and 15 at a portion adjacent to the body 24 of the robot 1 and at an intermediate portion, respectively, and a compliance mechanism 42 composed of an elastic member, such as a spring, and a six-axis force sensor 34 serving as a floor reaction force detecting means for detecting an actual floor reaction force acting on the ground contact portion 10 are provided in the vicinity of the distal portion of each of the legs #1 to #4 (a portion of the link connecting the spherical joint 12 and the joint 14, the

portion being adjacent to the spherical joint 12). In the example shown in the figure, the joints 14 permit rotation about two axes, while the joints 15 permit rotation about one axis. The bottom surfaces of the ground contact portions may be provided with elastic members made of sponge, rubber or the like serving as compliance mechanisms.

The displacement operation (the rotational operation about each axis) of each of the joints 14 and 15 is performed by an actuator, such as an electric motor, which is not shown. And, an actual joint displacement, which is the actual displacement amount (the angle of rotation about each axis), of each of the joints 14 and 15 is detected by a sensor, such as a rotary encoder, which is not shown. The six-axis force sensor 34 is capable of detecting the translational forces in the directions of three axes and the moments about three axes; however, in the robot 1 in the first embodiment, no actual floor reaction force moment acts on the central points of the ground contact portions 10, as described above. Hence, three-axis force sensors that detect the translational forces in the directions of three axes or force sensors that detect only the vertical components of the translational forces of actual floor reaction forces may be used in place of the six-axis force sensors 34.

The body 24 incorporates a control device 50 constructed of an electronic circuit unit that includes a

microcomputer, an actuator drive circuit, etc., a posture sensor 36 for detecting the postures of the body 24, and a power source not shown (a secondary battery, a capacitor, or the like). The posture sensor 36 is constructed of, for example, an acceleration sensor and a gyro sensor. In the present description, "posture" generally means a spatial orientation (however, "the posture" of the entire robot means an instantaneous value of a motion of the robot). Further, in the present embodiment, the posture sensor 36 detects the posture inclinations (inclination angles) in, for example, the pitch directions and roll directions in relation to the vertical direction, of the postures of the body 24. In other words, the posture sensor 36 functions as an actual posture inclination detecting means for detecting actual posture inclinations of the body 24.

If the postures (rotational angles) of the body 24 of the robot 1 also in the yaw direction are to be controlled, then the rotational angles of the body 24 in the yaw direction (in other words, the postures of the body 24 in the directions of three axes) may be also detected by the posture sensor 36.

Fig. 2 is a block diagram showing the functional construction and operations of the control device 50. The actual robot 1 shown in Fig. 2 is the robot 1 shown in Fig. 1 from which the control device 50, the posture sensor 36, and the six-axis force sensor 34 have been removed. Here,

a predetermined coordinate system (XYZ coordinate system) fixed to a floor, in which the approximately front direction of the robot 1 is defined as X axis, approximately left side direction thereof is defined as Y axis, and the upward direction thereof is defined as Z axis, as shown in Fig. 1, is referred to as "a supporting leg coordinate system" or "a global coordinate system." Hereinafter, positions, postures, translational forces and moments will be expressed in terms of coordinate components of the supporting leg coordinate system (the global coordinate system) unless otherwise specified. The origin of the supporting leg coordinate system (global coordinate system) does not have to be steadily fixed at a single point; the position of the origin with respect to a floor may be changed while the robot 1 is traveling. For example, the position of the origin of the supporting leg coordinate system (the global coordinate system) may be changed each time a predetermined leg of the robot 1 lands.

As shown in Fig. 2, the control device 50 is provided with a gait generating device 100, a desired floor reaction force distributor 102, a robot geometric model (inverse kinematics calculator) 110, a hierarchical compliance operation determiner 114, a displacement controller 112, an actual floor reaction force detector 108, a posture error calculator 103, and a posture stabilization control calculator 104 as its functional components (functional means). The following will explain

the overviews of the components of the control device 50.

The gait generating device 100 has a function as a desired gait determining means or a desired motion determining means in the present invention, and generates
5 (determines) and outputs a desired gait that specifies an operation of the robot 1. In the present embodiment, a desired gait is formed of the trajectory of a desired motion of the robot (the time series of a desired position/posture of each portion of the robot) and the
10 trajectory of a desired floor reaction force (the time series of a set of the desired position of the action point of a reaction force received by the robot from a floor and the desired values of a translational force and moment applied to the action point). In the present
15 description, "trajectory" means a time-series pattern (temporal change pattern).

The trajectory of a desired motion output by the gait generating device 100 is constructed of a desired ground contact portion trajectory, which is the trajectory
20 of the desired values of the position and the posture of each ground contact portion 10 of the robot 1, and a desired body position/posture trajectory, which is the trajectory of the desired values of the position and the posture of the body 24 of the robot 1. A gait generating
25 device in a robot equipped with joints related to arms or a head, as in a sixth embodiment to be discussed later, determines and outputs the desired position/posture

trajectories of the arms or the head as constituents of desired motions.

Further, in the present embodiment, the trajectory of a desired floor reaction force output by the gait
5 generating device 100 is formed of a desired total floor reaction force central point trajectory, which is the trajectory of a desired position of the total floor reaction force central point of the robot 1, and a desired total floor reaction force trajectory, which is the
10 trajectory of a desired value of a total floor reaction force that uses the above desired total floor reaction force central point as an action point. In the present embodiment, a desired total floor reaction force central point trajectory is regarded as identical to a desired ZMP
15 trajectory, which is the trajectory of a desired position of ZMP.

The position of each ground contact portion 10 is the position of a certain representative point of the ground contact portion 10, and the representative point is,
20 for example, the projected point obtained by projecting, in the vertical direction, the central point of each ground contact portion 10 (the central point of the spherical joint 12) onto the ground contact surface (bottom surface) of the ground contact portion 10, or the
25 central point of the ground contact portion 10 (the central point of the spherical joint 12). Hereinafter, the position of the representative point of each ground

contact portion 10 will be referred to simply as the ground contact portion position. The trajectory of a desired value of the ground contact portion position (a desired ground contact portion position trajectory) is included in the aforesaid desired ground contact portion trajectory determined by the gait generating device 100.

Here, in the robot 1 of the present embodiment, the ground contact portions 10 are engaged with the spherical joints 12, which are free joints, so that the postures of the ground contact portions 10 cannot be controlled. Therefore, according to the present embodiment, the gait generating device 100 does not actually generate the trajectories of desired postures of the ground contact portions 10 (does not have to generate them). In the present embodiment, therefore, the desired ground contact portion trajectory means the same as a desired ground contact portion position trajectory.

However, if the ground contact portions are attached to the distal portions of the legs such that their postures can be controlled (if the ground contact portions are attached to the distal portions of the legs through joints that can be operated by actuators), as in the robot of the sixth embodiment to be discussed later, then the trajectories of desired postures of the ground contact portions should be included in the desired ground contact portion trajectories. In the present description, the term "ground contact portion position/posture" will be

frequently used to generally consider the aforesaid case, the term substantially meaning "ground contact portion position" in the present embodiment.

Referring to Fig. 3(a) to Fig. 3(c) and Fig. 4(a) to Fig. 4(c), a desired ground contact portion trajectory (a desired ground contact portion position trajectory) and a desired total floor reaction force central point trajectory will be explained more specifically. According to the first embodiment, a travel of the robot 1 is accomplished by carrying out the motions of the legs #1 to #4 by causing a pair of legs, which are to be free legs, to leave a floor and move in the air and then land at a desired position by repeating, in order, a period during which the pair of the first leg #1 and the fourth leg #4 out of the legs #1 to #4 is a pair of supporting leg, while the pair of the second leg #2 and the third leg #3 is a pair of free legs, a period during which all legs #1 to #4 are supporting legs, and a period during which the pair of the first leg #1 and the fourth leg #4 is a pair of free legs, while the pair of the second leg #2 and the third leg #3 is a pair of supporting legs. A supporting leg is a leg that is in contact with the ground to support the self-weight of the robot 1 (a leg to be subject to a floor reaction force that is not zero), and a free leg is a non-supporting leg.

Fig. 3(a) to Fig. 3(c) and Fig. 4(a) to Fig. 4(c) show the desired ground contact portion positions (more

specifically, the positions on a horizontal plane (XY plane)) of the distal ends of the legs #1 to #4 during the aforesaid travel of the robot 1 in time series in sequence (in the sequence of time t_1 to t_6). The triangles
5 corresponding to reference characters Q1 to Q4 in these figures indicate the desired ground contact portion positions of the first to the fourth ground contact portions 10, respectively (the positions of the aforesaid representative points of the first to the fourth ground
10 contact portions 10 on a horizontal plane (XY plane)).

Supplementally, to be precise, the triangles with the reference characters Q1 to Q4 in Fig. 3 and Fig. 4 indicate the positions of desired node floor reaction force central points (desired ground contact portion floor
15 reaction force central points) to be discussed later, which are related to the ground contact portions 10. In the present embodiment, however, the representative points of the ground contact portions 10 are set as described above, so that the desired ground contact portion
20 positions (the desired positions of the representative points) of the first to the fourth ground contact portions 10 agree with the positions of the desired node floor reaction force central points Q_n ($n=1,2,3,4$), which will be discussed later, or have a certain positional
25 relationship with the positions of the respective desired node floor reaction force central points Q_n ($n=1,2,3,4$) (the positions on the horizontal plane (XY plane) agree).

For this reason, the triangles corresponding to the reference characters Q1, Q2, Q3 and Q4 in Fig. 3 and Fig. 4 denote the desired node floor reaction force central points, which will be discussed later, of the first to the fourth ground contact portions 10, respectively, and also denote the positions of the first to the fourth ground contact portions 10, respectively.

Fig. 3(a) shows the desired ground contact portion positions of the ground contact portions 10 at the instant (time t_1) when the pair of the first leg #1 and the fourth leg #4 as free legs are landed, the pair of the second leg #2 and the third leg #3 being supporting legs, Fig. 3(b) shows the desired ground contact portion positions at time t_2 in a state wherein all the legs #1 to #4 are supporting legs, and Fig. 3(c) shows the desired ground contact portion positions at time t_3 immediately before the pair of the second leg #2 and the third leg #3 as free legs is separated from a floor (lifted into the air), the pair of the first leg #1 and the fourth leg #4 being supporting legs. Further, Fig. 4(a) shows the desired ground contact portion positions at time t_4 in a state wherein the pair of the second leg #2 and the third leg #3 as free legs is lifted into the air, the pair of the first leg #1 and the fourth leg #4 being supporting legs, Fig. 4(b) shows the desired ground contact portion positions at the instant (time t_5) when the pair of the second leg #2 and the third leg #3 as free legs are landed, the pair of the first leg

#1 and the fourth leg #4 being supporting legs, and Fig. 4(c) shows the desired ground contact portion positions at time t_6 immediately before the pair of the first leg #1 and the fourth leg #4 as free legs is separated from a floor, the pair of the second leg #2 and the third leg #3 being supporting legs. Incidentally, in Fig. 4(a), the desired ground contact portion positions of the second leg #2 and the third leg #3, which are free legs, are indicated by dashed-line triangles. Supplementally, the trajectory of the positions of the ground contact portions of free legs in the vertical direction (the Z-axis direction) are determined such that they rise from a floor surface to a predetermined height and then lower to land again.

Point P in these Fig. 3 and Fig. 4 indicate desired total floor reaction force central points (desired ZMPs). The desired total floor reaction force central point trajectories are determined such that they continuously move while existing in a range in which ZMPs may exist (a region on a floor surface corresponding to a so-called supporting polygon) at positions not excessively close to the boundaries of the range (e.g., at an approximately central position of the range wherein a ZMP may exist). In the first embodiment, when two legs #1 and #4 or #2 and #3 are supporting legs (refer to Figs. 3(a) and (c) and Figs. 4(a) to (c)), a desired total floor reaction force central point is set on a segment connecting the

representative points of the ground contact portions 10 and 10 of those legs such that it is not excessively close to an end point of the segment. When all legs #1 to #4 are supporting legs (refer to Fig. 3(b)), a desired total floor reaction force central point is set within a polygon having the representative points of all ground contact portions 10 as its apex angles such that it is not excessively close to a boundary of the polygon. Fig. 5(d) is a graph illustrating a trajectory of a component ZMP_x in the X-axis direction (in the direction in which the robot 1 advances) of the position of the desired total floor reaction force central point (desired ZMP) determined as described above. Figs. 5(a) to (c) are graphs illustrating setting examples of weight, which will be discussed later.

Further, a desired body position/posture trajectory determined by the gait generating device 100 is determined using a dynamic model or the like of the robot 1 such that the horizontal component of a moment generated about a desired ZMP by the resultant force of the inertial force generated by a desired motion of the robot 1 and the gravity acting on the robot 1 becomes zero. Incidentally, "the body position" is the position of a certain representative point of the body 24.

A desired total floor reaction force determined by the gait generating device 100 is constructed of the desired values of the translational force and the moment

acting on a desired total floor reaction force central point, and it is determined such that it balances with the resultant force of the inertial force generated by a desired motion of the robot 1 and the gravity acting on the robot 1 at a desired total floor reaction force central point in the present embodiment. The moment horizontal component of the desired total floor reaction force about the desired total floor reaction force central point (desired ZMP) is zero. Supplementally, it is not necessary to determine all components of the translational force and the moment acting on the desired total floor reaction force central point as desired values. For instance, if the posture or the floor reaction force of the robot 1 about the vertical axis is not controlled, then it is not necessary to determine the component of the moment of the desired total floor reaction force about the vertical axis (the component in the Z-axis direction).

The desired ground contact portion trajectory determined by the gait generating device 100 (the desired ground contact portion position trajectory) is corrected by a hierarchical compliance operation determiner 114, which will be discussed later.

The desired floor reaction force distributor 102 groups (that is, hierarchizes) the first to the fourth ground contact portions 10 of the robot 1 into a tree structure, and associates the nodes of the tree structure with each of the hierarchized groups. Hence, in the

following explanation, the nodes may be expressed by replacing them by the groups. Each node is a group constructed of one or more ground contact portions 10.

5 In the first embodiment, the ground contact portions 10 are hierarchized, as shown in Fig. 6. More specifically, the n-th ground contact portion 10 ($n=1,2,3,4$) is associated with the n-th node, the node having a first node and a fourth node as child nodes is defined as a 14th node, the node having a second node and a third node as child nodes is defined as a 23rd node, and 10 the node having the 14th node and the 23rd node as child nodes is defined as the 1423rd node. Thus, the first to the fourth nodes are nodes that are constructed of the first, the second, the third, and the fourth ground 15 contact portions 10, respectively, the 14th node is a node constructed of the first ground contact portion 10 and the fourth ground contact portion 10, the 23rd node is a node constructed of the second ground contact portion 10 and the third ground contact portion 10, and the 1423rd node 20 is the node constructed of all the ground contact portions 10.

According to general designations in a tree structure, a node having no child node is referred to as a leaf node, and a node having no parent node is referred to 25 as a root node. Thus, the n-th node ($n=1,2,3,4$) is a leaf node, while the 1423rd node is a root node. In the present description, to identify nodes, leaf nodes will be

assigned the same numbers (1,2,3,...) as those of the ground contact portions (or legs) associated therewith, while nodes other than the leaf nodes will be assigned with numbers that are greater than those of the leaf nodes.

5 Further, the nodes other than the leaf nodes and the root node will be referred to as intermediate nodes. In the first embodiment, the intermediate nodes are the 14th node and the 23rd node.

Input to the desired floor reaction force distributor 102 are a desired total floor reaction force central point trajectory, a desired total floor reaction force trajectory and a desired ground contact portion trajectory out of a desired gait determined by the gait generating device 100. The gait parameters (the estimated landing position, an estimated landing time, etc. of the ground contact portion 10 of a free leg of the robot 1) used by the gait generating device 100 to determine the desired gait may be also input to the desired floor reaction force distributor 102. Then, on the basis of these inputs, the desired floor reaction force distributor 102 determines desired node floor reaction force central points (desired n-th node floor reaction force central points) Q_n ($n=1,2,3,4,14,23,1423$), which are the desired positions of the floor reaction force central points of the nodes hierarchized as described above, and weights W_n ($n=1,2,3,4,14,23$) of the nodes except the root node. Each weight W_n will be a nonnegative value of 1 or less.

The technique for determining desired node floor reaction force central points Q_n ($n=1,2,3,4,14,23$) and the weights W_n ($n=1,2,3,4,14,23$) will be explained in detail below with reference mainly to Fig. 3(b), Fig. 5 and Fig. 7. Fig. 3(b) shows a relationship between Q_n and W_n in a state illustrated in the figure, Figs. 5(a) to (c) show setting examples of W_n , and Fig. 7 shows a relationship between weights and desired node floor reaction force central points.

The desired node floor reaction force central point of the 1423rd node, which is the root node, (the desired 1423rd node floor reaction force central point) Q_{1423} is determined to be identical to the desired total floor reaction force central point (point P in Fig. 3 and Fig 4) ($P=Q_{1423}$). Accordingly, in the following explanation, the same reference character P as that of a desired total floor reaction force central point will be frequently used as the mark denoting the desired 1423rd node floor reaction force central point.

Further, a weight W_{1423} of the root node is set to "1" for the sake of convenience in order to maintain the uniformity of expressions.

In the present embodiment, the desired floor reaction force central point of an n-th ground contact portion 10 ($n=1,2,3,4$) (also referred to as a desired n-th ground contact portion floor reaction force central point) is always set to the central point of an n-th ground

contact portion 10 (the central point of the spherical joint 12). Further, the desired node floor reaction force central point Q_n ($n=1,2,3,4$) of a leaf node associated with the n -th ground contact portion 10 is determined to be identical to the desired floor reaction force central point of the n -th ground contact portion 10. Hence, the desired node floor reaction force central point Q_n ($n=1,2,3,4$) is also always set to the central point of the n -th ground contact portion 10 (the position of this point is uniquely determined from a desired ground contact portion position of the n -th ground contact portion 10). The position of the desired node floor reaction force central point Q_n ($n=1,2,3,4$) of the leaf node determined as described above is uniquely determined from the desired ground contact portion position of the n -th ground contact portion 10. In other words, the desired node floor reaction force central point Q_n ($n=1,2,3,4$) of a leaf node defines the desired position of the n -th ground contact portion 10. In the following explanation, the desired node floor reaction force central point of a leaf node may be referred to as a desired ground contact portion floor reaction force central point in some cases. Each desired ground contact portion trajectory is set such that it continuously changes, so that Q_n ($n=1,2,3,4$) will also continuously change.

Supplementally, in the present embodiment, the desired floor reaction force central point Q_n ($n=1,2,3,4$)

of an n-th leaf node (an n-th ground contact portion 10) has been set to the central point of the n-th ground contact portion 10; however, in a robot that allows the postures of ground contact portions to be controlled, the desired floor reaction force central point of each leaf node (each ground contact portion) may be set, for example, within the ground contact surface of the ground contact portion defined by the desired position/posture of the ground contact portion associated with the leaf node (the surface that comes in contact with a floor surface assumed in a desired gait).

Hereinafter, in general, a segment that connects arbitrary two points A and B or the length thereof will be denoted as AB. In addition, an operator "*" means multiplication for a pair of scalar and scalar or a pair of scalar and vector, while it means an outer product (vector product) for a pair of vector and vector.

The weight W_n ($n=1,2,3,4,14,23$) of each node except the root node and desired node floor reaction force central points Q_{14} and Q_{23} of the intermediate nodes are determined such that a desired 14th node floor reaction force central point Q_{14} will be the internally dividing point of a segment Q_1Q_4 that satisfies a relational expression, $Q_1Q_{14}:Q_{14}Q_4=W_4:W_1=(1-W_1):W_1$, a desired 23rd node floor reaction force central point Q_{23} will be the internally dividing point of a segment Q_2Q_3 that satisfies a relational expression, $Q_2Q_{23}:Q_{23}Q_3=W_3:W_2=(1-W_2):W_2$, and

a desired 1423rd node floor reaction force central point P (= desired total floor reaction force central point) will be the internally dividing point of a segment Q14Q23 that satisfies $Q14P:PQ23=W23:W14=(1-W14):W14$.

5 In other words, Q14, Q23 and Wn (n=1,2,3,4,14,23) are determined to satisfy at least the following expressions 1, 2 and 3. Incidentally, Qn (n=1,2,3,4,14,23) in these expressions 1 to 3 means the position (positional vector) of the point.

10

Q14=Q1*W1+Q4*W4 , W1+W4=1 ... Expression 1
Q23=Q2*W2+Q3*W3 , W2+W3=1 ... Expression 2
P=Q14*W14+Q23*W23 , W14+W23=1 ... Expression 3

15 Wn (n=1,2,3,4,14,23) takes a nonnegative value of 1 or less, so that the coefficients (weights) of Qn (n=1,2,3,4,14,23) in the right sides of the above expressions 1, 2 and 3 will be all nonnegative values.

20 The above expressions 1 to 3 mean that the position of a desired node floor reaction force central point of each node having child nodes (that is, each node that is not a leaf node) is set to a weighted average position of the position of the desired node floor reaction force central points of the child nodes of the node by using a
25 predetermined nonnegative weight. In other words, as shown in Fig. 3(b) and Fig. 7 mentioned above, the desired floor node reaction force central point Qn (n=14,23,1423)

of each node having child nodes is set at the internally
dividing point of the desired node floor reaction force
central points of all the child nodes of the node. Fig. 7
is a diagram showing a relationship between the desired
node floor reaction force central points Q_n
($n=1,2,3,4,14,23,1423$) of nodes and the weight W_n
($n=1,2,3,4,14,23$). Incidentally, L_{23} , L_{14} and L_{1423} in
Fig. 3(b) denote segments Q_2Q_3 , Q_1Q_4 and $Q_{23}Q_{14}$,
respectively.

Supplementally, Q_1 to Q_4 and $P (=Q_{1423})$ are
determined as described above, so that once W_n
($n=1,2,3,4,14,23$) is determined, Q_{14} and Q_{23} that satisfy
expressions 1 to 3 are uniquely determined. In other
words, if Q_{14} and Q_{23} are determined, then W_n
($n=1,2,3,4,14,23$) satisfying expressions 1 to 3 will be
uniquely determined. Accordingly, the weight W_n
($n=1,2,3,4,14,23$) may be determined and then the desired
node floor reaction force central points Q_{14} and Q_{23} of
intermediate nodes according to the above expressions 1 to
3 may be determined, or the desired node floor reaction
force central points Q_{14} and Q_{23} of the intermediate node
may be determined and then the weight W_n ($n=1,2,3,4,14,23$)
may be determined according to the above expression 1 to 3.
Either way may be used.

The desired node floor reaction force central points
 Q_{14} and Q_{23} of the intermediate nodes move as the ground
contact portions 10 move, as shown in time series in Fig.

3(a) to Fig. 3(c) and Fig. 4(a) to Fig. 4(c). Weights W_{14} ($=1-W_{23}$), W_1 ($=1-W_4$) and W_3 ($=1-W_2$) at this time are determined such that they continuously change, as shown in, for example, the graphs of Figs. 5(a) to (c), respectively.

5 The trajectory of Q_n and the weight W_n of the n -th node ($n=1,2,3,4$) are set such that they continuously change, so that the desired node floor reaction force central points Q_{14} and Q_{23} are also set such that they continuously move. This means that all desired node floor reaction force
10 central points (desired n -th node floor reaction force central points ($n=1,2,3,4,14,23,1423$)) are set such that they continuously move.

The desired floor reaction force distributor 102 outputs the desired node floor reaction force central
15 point of each node determined as described above. The desired floor reaction force central point of the root node is the same as the desired total floor reaction force central point determined by the gait generating device 100, so that it does not have to be output from the desired
20 floor reaction force distributor 102.

The desired floor reaction force distributor 102 determines and outputs a desired node floor reaction force, which is the desired value of the floor reaction force acting on the desired floor reaction force central point
25 of each node. The desired node floor reaction force that is output includes at least a desired node floor reaction force (a desired n -th node floor reaction force) acting on

a desired node floor reaction force central point Q_n of an n -th node ($n=1,2,3,4$), which is a leaf node, that is, the desired floor reaction force of each ground contact portion 10. This desired node floor reaction force is
5 necessary primarily to compensate for the flexures of the compliance mechanisms 42 or the like (refer to Fig. 1) of the legs #1 to #4 (more specifically, compensation for the positional displacement of the ground contact portions 10 caused by the flexures of the compliance mechanisms 42 and
10 the link mechanisms of the legs), the compensation being carried out by the processing of a hierarchical compliance operation determiner 114, which will be discussed later. Supplementally, if the robot 1 is provided with compliance mechanisms in addition to those on the distal portions of
15 the legs #1 to #4, then preferably, a desired 14th node floor reaction force and a desired 23rd node floor reaction force (the desired node floor reaction forces of intermediate nodes) are also determined and output in order to determine the deformations of the compliance
20 mechanisms.

Generally, a desired floor reaction force (a desired node floor reaction force) acting on a desired node floor reaction force central point of each node may be determined from a desired total floor reaction force and
25 the weight of each node. Specifically, the desired floor reaction force of any one node may be determined by multiplying the product of the weight of the node and the

weight of all ancestor nodes of the node by a desired total floor reaction force. More specifically, a desired n-th node floor reaction force is calculated according to the following expression 4a (or expression 4b).

5

Desired n-th node floor reaction force

= Weight of the n-th node

* Product of the weights of all ancestor nodes of the n-th node

10

* Desired total floor reaction force ... Expression 4a

Desired n-th node floor reaction force

= Weight of the n-th node

* Product of the weight of all ancestor nodes (excluding the root node) of the n-th node

15

* Desired total floor reaction force ... Expression 4b

Alternatively, desired node floor reaction forces are determined such that the desired floor reaction force of an arbitrary n-th node that is not a leaf node agrees with the sum (resultant force) of the desired floor reaction forces of all child nodes of the n-th node and the desired floor reaction force of the root node agrees with a desired total floor reaction force. This relationship is shown in Fig. 8.

20

25

More specifically, if a desired n-th node floor reaction force, which is the desired floor reaction force of an n-th node, is denoted by F_n ($n=1,2,3,4,14,23,1423$)

and a desired total floor reaction force is denoted by $F_{totalref}$, then F_n is determined from $F_{totalref}$ and the weight W_n ($n=1,2,3,4,14,23$) according to the expressions shown in Fig. 8. The expressions in Fig. 8 are equivalent to the above expression 4a or 4b.

Determining the desired floor reaction force central point of each node (a desired node floor reaction force central point) and the desired floor reaction force of each node (a desired node floor reaction force) as described above is to determine the desired floor reaction force central point and the desired floor reaction force of each node such that the horizontal component of the moment generated about a desired n -th node floor reaction force central point by the resultant force of the desired floor reaction forces of all child nodes of an n -th node becomes zero. Accordingly, the moment horizontal component of a desired node floor reaction force is zero for any nodes.

A set of each desired node floor reaction force central point Q_n ($n=1,2,3,4,14,23$), each weight W_n ($n=1,2,3,4,14,23$) and each desired node floor reaction force F_n ($n=1,2,3,4,14,23$) is determined such that the desired floor reaction force of the ground contact portion not in contact with the ground (in a no-contact-with-ground state) (the desired node floor reaction force of a leaf node associated with the ground contact portion not in contact with the ground) is zero. Hence, in the

first embodiment, the weight W_{14} is set to zero ($W_{23}=1$) during a period in which the first ground contact portion 10 and the fourth ground contact portion 10 are free legs and off a floor (the ground contact portions 10 of the free legs are moving in the air), while the weight W_{23} is set to zero ($W_{14}=1$) during a period in which the second ground contact portion 10 and the third ground contact portion 10 are free legs and off a floor, as shown in Fig. 5(a). Thus, the weight of an intermediate node having child nodes is set to zero during a period in which none of the ground contact portions belonging as leaf nodes to the intermediate node are in contact with the ground. In other words, the weight of an intermediate node is not set to zero during a period in which any one of the ground contact portions belonging to the intermediate node is in contact with the ground (strictly speaking, a period during which a non-zero floor reaction force is acting on any one of the ground contact portions).

Supplementally, the first embodiment does not have a period during which only one of the first ground contact portion 10 and the fourth ground contact portion 10 belonging to the intermediate node Q_{14} is placed in a no-contact-with-ground state; therefore, the weights W_1 and W_4 corresponding to these ground contact portions 10 and 10 do not have any periods during which they are 0 or 1. If, however, a desired ground contact portion trajectory is determined so as to include a period during which only

one of the first ground contact portion 10 and the fourth ground contact portion 10 will be placed in the no-contact-with-ground state, then the weight associated with the ground contact portion 10 that will be placed in the no-contact-with-ground state during the period may be set to 0, and the weight associated with the ground contact portion 10 to be in contact with the ground may be set to 1. In this case, the weight of the intermediate node Q14 during that period will be set to a non-zero value. The same applies to the weights associated with the intermediate node Q23 and the second ground contact portion 10 and the third ground contact portion 10, which are leaf nodes belonging thereto. Generally speaking, the weight of a node having child nodes is set to a non-zero value if any one of the ground contact portions belonging to the node is in contact with the ground, while it is set to zero if all of the ground contact portions belonging to the node are in no-contact-with the ground.

The desired node floor reaction forces determined as described above continuously change, making them suited for achieving a movement (walking) of the robot 1 with less impact.

As described above, according to the first embodiment, each desired node floor reaction force central point Q_n ($n=1,2,3,4,14,23,1423$), each weight W_n ($n=1,2,3,4,14,23$) and each desired each floor reaction force F_n ($n=1,2,3,4,14,23,1423$) are determined by the

desired floor reaction force distributor 102 such that they satisfy the following conditions A) to G).

A) The desired node floor reaction force central point Q_n ($n=1,2,3,4$) of each leaf node agrees with the central point of the ground contact portion 10 corresponding to the leaf node. More generally, Q_n ($n=1,2,3,4$) is determined according to a desired gait (a desired motion, such as a desired ground contact portion trajectory).

Supplementally, for example, the desired floor reaction force central point of each ground contact portion 10 may be determined by the gait generating device 100, and in this case, the desired node floor reaction force central point Q_n ($n=1,2,3,4$) may be determined on the basis of the desired floor reaction force determined by the gait generating device 100.

B) The desired node floor reaction force central point of the root node agrees with a desired total floor reaction force central point P.

C) The desired node floor reaction force central point Q_n ($n=1,2,3,4,14,23$) and the weight W_n ($n=1,2,3,4,14,23$) of each node excluding the root node satisfy the relational expressions of the above expressions 1 to 3. In other words, the desired node floor reaction force central point Q_n of an arbitrary n -th node ($n=14,23,1423$) having child nodes will be a weighted average point of the desired node floor reaction force central points of the child nodes of the n -th node.

D) The desired node floor reaction force F_n of an arbitrary n -th node ($n=14,23,1423$) having child nodes agrees with the sum (resultant force) of the desired node floor reaction forces of all child nodes of the n -th node, and the desired node floor reaction force F_{1423} of the root node (the 1423rd node) agrees with the desired total floor reaction force $F_{totalref}$. In other words, the desired floor reaction force F_n and the weight W_n of the n -th node ($n=1,2,3,4,14,23,1423$) satisfy the relational expressions in Fig. 8.

E) The desired node floor reaction force of a leaf node associated with the ground contact portion 10 not in contact with the ground is zero.

F) Q_n , W_n , and F_n ($n=1,2,3,4,14,23,1423$) continuously change.

G) The weight of a leaf node corresponding to the ground contact portion 10 in a no-contact-with-ground state or the weight of any one of the ancestor nodes of the leaf node is zero.

Incidentally, a desired node floor reaction force may be determined on the basis of each desired node floor reaction force central point in place of determining it on the basis of a weight as described above. More specifically, each desired node floor reaction force central point may be determined such that the aforesaid conditions A) to C) are satisfied, then each weight may be determined on the basis of the desired node floor reaction

force central point and the aforesaid expressions 1 to 3, and then the desired node floor reaction force may be determined according to the aforesaid expression 4 by using the determined weight.

5 Returning to the explanation of Fig. 2, the posture error calculator 103 calculates the error of an actual body posture with respect to a desired body posture and outputs the calculated error to the robot 1. In the present embodiment, the posture error calculator 103
10 receives an inclination angle of the body 24 relative to the vertical direction detected by the posture sensor 36 (hereinafter referred to as the actual body posture inclination) and a desired body position/posture determined by the gait generating device 100 (specifically,
15 the inclination angle in a desired body posture relative to the vertical direction; hereinafter referred to as the desired body posture inclination), and then calculates an error θ_{berr} between them (Actual body posture inclination - Desired body posture inclination; hereinafter referred
20 to as the body posture inclination error θ_{berr}). The calculated θ_{berr} is composed of a component about the X axis (the component in the roll direction) θ_{berrx} and a component about the Y axis (the component in the pitch direction) θ_{berry} . If a desired body posture inclination
25 is, for example, steadily zero, then θ_{berr} =actual body posture inclination, so that a detected value (actual body posture inclination) of a posture sensor 36 may be

directly output as the body posture inclination error θ_{berr} .

Generally speaking, the posture stabilization control calculator 104 calculates a compensating total floor reaction force, which is a compensation amount of a total floor reaction force (the correction amount of a desired total floor reaction force) for stabilizing the posture of the robot 1 according to the state of the robot 1 that is detected or estimated on the basis of the information of a sensor provided in the robot 1, such as the aforesaid body posture inclination error.

To stabilize the posture of the robot 1 in the long term, a translational force and a moment necessary to restore the actual position/posture of a predetermined portion, such as the body 24, of the robot 1 to a desired position/posture are determined, and these have to be additionally generated at the desired total floor reaction force central point (desired ZMP) being the point of action. The additional translational force and moment are referred to as a compensating total floor reaction force. The moment component of a compensating total floor reaction force is referred to as a "compensating total floor reaction force moment M_{dmd} (specifically, a compensating total floor reaction force moment M_{dmd} about a desired total floor reaction force central point (desired ZMP)).

In the present embodiment, the posture stabilization

control calculator 104 calculates the compensating total floor reaction force moment M_{dmd} so as to restore (approximate) an actual body posture inclination to a desired body posture inclination. Hence, the body posture inclination errors θ_{berr} (θ_{berrx} , θ_{berry}) determined by the posture error calculator 103 are input to the posture stabilization control calculator 104.

The posture stabilization control calculator 104 calculates the compensating total floor reaction force moment M_{dmd} on the basis of the input body posture inclination error θ_{berr} . The calculated M_{dmd} is composed of a component about the X axis M_{dmdx} and a component about the Y axis M_{dmdy} .

Specifically, M_{dmdx} and M_{dmdy} are determined by, for example, the feedback control law (PD control law here) of expressions 5 and 6 given below. More specifically, M_{dmdx} and M_{dmdy} are determined so as to approximate the body posture inclination errors θ_{berrx} and θ_{berry} to zero.

$$M_{dmdx} = -K_{thx} \cdot \theta_{berrx} - K_{wx} \cdot (d\theta_{berrx}/dt) \quad \dots \text{Expression 5}$$

$$M_{dmdy} = -K_{thy} \cdot \theta_{berry} - K_{wy} \cdot (d\theta_{berry}/dt) \quad \dots \text{Expression 6}$$

where K_{thx} , K_{thy} , K_{wx} and K_{wy} denote predetermined gains. Further, $(d\theta_{berrx}/dt)$ and $(d\theta_{berry}/dt)$ denote the time differential values of the body posture inclination errors θ_{berrx} and θ_{berry} , respectively.

In the present embodiment, a component of the

compensating total floor reaction force moment M_{dmd} about the Z axis (the component in the yaw direction) M_{dmdz} is not used, so that M_{dmdz} is not determined; however, M_{dmdz} may be determined to prevent the robot 1 from spinning

5 (slippage about the vertical axis). A method for determining M_{dmdz} is explained in detail in Japanese Patent Application No. 2003-185613 or Japanese Patent Application No. 2003-185930 previously proposed by the present applicant. Moreover, for example, to restore the
10 position of an actual center-of-gravity of the robot 1 to the position of the center-of-gravity in a desired gait, the translational force of a compensating total floor reaction force can be determined on the basis of a positional error of the center-of-gravity.

15 The floor reaction force detector 108 detects the actual floor reaction forces, which are the actual values of the floor reaction forces acting on the ground contact portions 10 of the actual robot 1 (that is, the actual floor reaction forces of leaf nodes (actual node floor
20 reaction forces)) on the basis of the outputs of the six-axis force sensor 34 of the legs #1 to #4. In addition, the floor reaction force detector 108 calculates the relative positions/postures (the relative positions in the first embodiment) of the ground contact portions 10
25 relative to the coordinate system fixed to the body 24 on the basis of the actual joint displacements of the joints 14 and 15 (the actual rotational angles of the joints 14

and 15 about individual rotational axes) of the legs #1 to #4 detected by sensors, such as encoders, (not shown) provided on the joints 14 and 15 of the robot 1. At this time, joint displacement commands, which are the displacement command values (rotational angle command values) of the joints 14 and 15 may be used in place of actual joint displacements, or both actual joint displacements and joint displacement commands may be used. Then, based on the calculated relative positions/postures of the ground contact portions 10, the detected values of the six-axis force sensor 34 of the legs #1 to #4 (these being the values on a local coordinate system fixed to the six-axis force sensor 34 or the like) are coordinate-converted to calculate actual floor reaction forces represented on the coordinate system fixed to the body 24, and then the calculated actual floor reaction forces are converted into the actual floor reaction forces represented on a supporting leg coordinate system (global coordinate system). For the coordinate conversion into the supporting leg coordinate system, detected values of the posture sensor 36 or desired body posture inclinations may be used. Supplementally, in the robot 1 according to the first embodiment, no floor reaction force moment acts on the central points of the ground contact portions 10, as described above, so that there is no need to detect a moment component in the actual floor reaction force of each ground contact portion 10. In this case, as

mentioned above, in place of the six-axis force sensor 34, a three-axis force sensor may be used to detect translational force components of actual floor reaction forces in three axes, or a one-axis floor reaction force sensor may be used to detect only translational force vertical components of actual floor reaction forces.

Based on a final desired trajectory of each ground contact portion position/posture (this being determined by a hierarchical compliance operation determiner 114, which will be discussed later) and desired body position/posture or the like, the robot geometric model (inverse kinematics calculator) 110 performs inverse kinematics calculation to calculate joint displacement commands, which are the command values of the displacements (rotational angles) of the joints 14 and 15 of the robot 1, that satisfy the above. In the present embodiment, the equation of the solution of the inverse kinematics calculation has been determined beforehand, and the joint displacement commands have been calculated simply by substituting desired body position/posture and the final desired position of each ground contact portion into the equation. More specifically, the robot geometric model 110 receives a desired body position/posture trajectory determined by the gait generating device 100 and a corrected desired ground contact portion trajectory corrected as will be discussed later by the hierarchical compliance operation determiner 114 (a corrected desired ground contact portion trajectory

with deformation compensation), and calculates the joint displacement commands of the joints 14 and 15 of the legs #1 to #4 by the inverse kinematics calculation from the received values.

5 In the case of a robot having joints, such as arm joints and a neck joint, in addition to leg joints, as in the sixth embodiment to be discussed later, the displacements of joints other than the leg joints are determined by the inverse kinematics calculation on the
10 basis of the relative positions/postures of hands, the head or the like with respect to the body.

 The displacement controller 112 receives the actual joint displacements (detected values) of the joints 14 and 15 of the robot 1 and the joint displacement commands
15 calculated by the robot geometric model (inverse kinematics calculator) 110, and controls (feedback-control) actuators (not shown) of the joints 14 and 15 by using the joint displacement commands as the desired values such that the actual joint displacements follow the
20 desired values.

 The hierarchical compliance operation determiner 114 corrects a desired ground contact portion trajectory to approximate an actual total floor reaction force to the resultant force of a desired total floor reaction force
25 and a compensating total floor reaction force, and outputs a corrected desired ground contact portion position/posture trajectory with deformation compensation,

which is the desired ground contact portion trajectory after the correction. In the present embodiment, the postures of the ground contact portions 10 cannot be controlled; therefore, the corrected desired ground contact portion position/posture trajectory with deformation compensation is actually a corrected desired ground contact portion position trajectory with deformation compensation.

The hierarchical compliance operation determiner 114 generally corrects the desired ground contact portion trajectories of the ground contact portions 10 so as to satisfy the following three requirements as much as possible.

Requirement 1) In order to stabilize the position/posture of the robot 1, an actual total floor reaction force is made to follow the resultant force of a compensating total floor reaction force (moment M_{dmd}) output by the posture stabilization control calculator 104 and a desired total floor reaction force. According to the first embodiment, in order to stabilize the posture inclination (the inclination relative to the vertical direction) of the body 24 of the robot 1, the horizontal component of an actual total floor reaction force moment about a desired total floor reaction force central point is made to follow horizontal components M_{dmdx} and M_{dmdy} of the compensating total floor reaction force moment M_{dmd} . Supplementally, the horizontal component of the desired total floor

reaction force moment about the desired total floor
reaction force central point is zero, so that the
resultant force of this and M_{dmd} agrees with M_{dmd} .

Requirement 2) The absolute value of the actual floor

5 reaction force moment about a desired floor reaction force
central point of each node, which is not a leaf node, is
minimized as much as possible to prevent an actual floor
reaction force from being focused on some ground contact
portions 10 of a plurality of ground contact portions 10
10 to be in contact with the ground, causing the actual floor
reaction force on other ground contact portions 10 to be
excessively reduced, which will lead to extremely
deteriorated ground contacting properties of the ground
contact portions 10 having the reduced actual floor
15 reaction force. In the first embodiment, the absolute
values of the actual floor reaction force moments about
the desired floor reaction force central points of the
14th node, the 23rd node and the 1423rd node are minimized
as much as possible.

20 Requirement 3) In order to secure the ground contacting
properties of the ground contact portions 10 to be in
contact with the ground, that is, to prevent local ground
contacting properties of the ground contact portions 10
from deteriorating due to uneven local ground contact
25 pressure distribution (the distribution of an actual floor
reaction force) in the ground contact portions 10, the
absolute values of the actual floor reaction force moments

about the desired floor reaction force central points of the ground contact portions 10 (leaf nodes) are minimized as much as possible. However, in the robot 1 of the first embodiment, the actual floor reaction force moments about the desired floor reaction force central points of the ground contact portions 10 are always zero; therefore, it is unnecessary to consider this requirement 3).

In general, it is impossible to fully satisfy all of requirements 1) to 3) or requirements 1) and 2). For example, it is often physically impossible to zero the actual floor reaction force moments about the desired floor reaction force central points of the ground contact portions 10 while making an actual total floor reaction force agree with the resultant force of a compensating total floor reaction force and a desired total floor reaction force. Hence, the hierarchical compliance operation determiner 114 usually corrects the desired ground contact portion trajectories of the ground contact portions 10 at certain compromise points while satisfying requirements 1) to 3) or requirements 1) and 2) as much as possible.

The above has given the overviews of the functional means (functional components) of the control device 50.

Supplementally, the hierarchical compliance operation determiner 114, the posture stabilization control calculator 104 and a robot geometric model (inverse kinematics calculator) 110 correspond to the node

operation control means in the present invention.

Referring now to the flowchart of Fig. 9, the overall operation (arithmetic processing) of the control device 50 will be explained in more detail. Fig. 9 is a flowchart (structured flowchart) showing the main routine processing of the control device 50. The components of the control device 50 carrying out pertinent processing are shown on the left in Fig. 9.

First, the initialization of the control device 50 is performed in S10, then the processing advances to S14 via S12. The arithmetic processing of the control device 50 waits for a timer interrupt for each control cycle. The control cycle is, for example, 50 ms.

Subsequently, the processing proceeds to S16 wherein it determines whether a gait change is observed, and if the determination result is NO, then it proceeds to S22, which will be discussed later. If the determination result in S16 is YES, then the processing proceeds to S18 wherein it initializes time t to zero, and proceeds to S20 wherein it sets gait parameters. In the present embodiment, for example, a desired gait of a predetermined period from the moment a predetermined leg (e.g., #1) of the robot 1 leaves a floor to the moment it leaves the floor next (or from the moment it lands to the moment it lands next) is taken as a unit, and gait parameters that are the parameters defining the desired gait for the predetermined period (the parameters used in the algorithm

for determining the desired gait) are set in S20. The
"gait change" mentioned in S16 means the change of the
desired gait for the predetermined period. Whether the
desired gait is changing may be determined mainly on the
basis of time or a detected value of the six-axis force
sensor 34 on the predetermined leg.

The gait parameters set in S20 are composed of
motion parameters that define the desired motion
trajectories (specifically, a desired ground contact
portion trajectory and a desired body position/posture
trajectory) of the robot 1 and the floor reaction force
parameters that define desired floor reaction force
trajectories (specifically, a desired total floor reaction
force trajectory and a desired total floor reaction force
central point trajectory). Supplementally, once the
desired motion of the robot 1 is determined, the desired
total floor reaction force can be obtained by reversing
the sign of the resultant force of the inertial force
generated by the desired motion and the gravity acting on
the robot 1, so that the floor reaction force parameters
may be the ones that define only a desired total floor
reaction force central point trajectory. Further, motion
parameters do not have to include parameters that define a
desired body position/posture trajectory if a desired
ground contact portion trajectory (more generally, the
parameter of a desired motion other than desired body
position/posture) and a desired total floor reaction force

central point are determined, and then desired body position/posture are determined using a dynamic model of the robot 1 such that the horizontal component of a moment generated about a desired total floor reaction force central point (desired ZMP) by the resultant force of the inertial force generated by a desired motion, including desired body position/posture of the robot 1, and the gravity acting on the robot 1 becomes zero.

Subsequently, the processing proceeds to S22 wherein the instantaneous value of a desired gait is determined on the basis of the aforesaid gait parameters. Here, "instantaneous value" means a value for each control cycle, and a desired gait instantaneous value is composed of the instantaneous values of desired body position/posture, a desired ground contact portion position (the instantaneous value of a desired ground contact portion trajectory), a desired total floor reaction force, and a desired total floor reaction force central point position (a desired ZMP position). In the present embodiment, the postures of the ground contact portions 10 cannot be controlled, so that the instantaneous values of the desired postures of the ground contact portions 10 are not determined. In a case where the postures of the ground contact portions can be controlled, the parameters defining the desired postures of the ground contact portions may be included in the gait parameters and the instantaneous values of the desired postures of the ground contact portions may be determined

on the basis of the parameters.

The processing of S14 to S22 described above is the processing carried out by the gait generating device 100.

Subsequently, the processing proceeds to S24 wherein
5 the weight $W_n(n=1,2,3,4,14,23)$ of each node and a desired floor reaction force central point of each node (a desired node floor reaction force central point)
 $Q_n(n=1,2,3,4,14,23)$ are determined. This processing is the processing carried out as described above by the
10 desired floor reaction force distributor 102.

Subsequently, the processing proceeds to S26 wherein desired node floor reaction forces (including at least the desired floor reaction forces of the ground contact portions 10 (leaf nodes)) are determined. In the first
15 embodiment, the desired node floor reaction forces of leaf nodes (desired ground contact portion floor reaction forces) are determined. This processing of S26 is also the processing carried out as described above by the desired floor reaction force distributor 102. As
20 described above, if the compliance mechanisms are provided on other portions in addition to the distal portions of the legs #1 to #4, then the desired floor reaction forces of intermediate nodes that are not leaf nodes should be also determined. Supplementally, the moment horizontal
25 component of a desired node floor reaction force is zero.

Subsequently, the processing proceeds to S28 wherein the state of the robot 1, such as the actual body posture

inclination, is detected from an output of the posture sensor 36 or the like. In the first embodiment, the value of an actual body posture inclination detected by the posture sensor 36 is captured by the posture error calculator 103, and a body posture inclination error θ_{berr} is calculated from the detected value and the desired body posture inclination (the instantaneous value at the current time) out of the desired body position/posture.

Subsequently, the processing proceeds to S30 wherein a compensating total floor reaction force for stabilizing the posture of the robot 1 is determined from the state of the robot 1 detected in S28. In the first embodiment, the horizontal components $Mdmdx$ and $Mdmdy$ of a compensating total floor reaction force moment $Mdmd$ about a desired total floor reaction force central point (desired ZMP) are calculated by the posture stabilization control calculator 104 from the body posture inclination error θ_{berr} according to the above expression 5 and expression 6.

Subsequently, the processing proceeds to S32 wherein the actual floor reaction force of each ground contact portion 10 is detected. This is the processing carried out by the actual floor reaction force detector 108. As described above, the actual floor reaction force for each ground contact portion 10 detected by the six-axis force sensor 34 that is converted to a supporting leg coordinate system (global coordinate system) is determined. Hereinafter, the actual floor reaction force of each

ground contact portion 10 may be referred to as an actual ground contact portion floor reaction force in some cases.

Subsequently, from S34 to S38, the processing of the hierarchical compliance operation determiner 114 is carried out.

For a while, the following will explain the overall processing of the hierarchical compliance operation determiner 114 before the processing of these S34 to S38 is specifically explained. In this explanation, for the convenience of understanding, the state shown in Fig. 3(b) mentioned above (the state wherein all the legs #1 to #4 of the robot 1 are supporting legs) will be primarily taken as an example.

The hierarchical compliance operation determiner 114 determines the translational force components and moment components of the desired node floor reaction forces of nodes excluding leaf nodes (more specifically, the translational force components and the moment components that have desired node floor reaction force central points as the points of action) mainly on the basis of the desired node floor reaction forces of the leaf nodes determined by the desired floor reaction force distributor 102.

The translational force components of the desired floor reaction forces (desired node floor reaction forces) of the nodes in the state shown in Fig. 3(b) are illustratively shown in Fig. 10. In this figure, a vector

F_{n_ref} ($n=1,2,3,4,14,23$) denotes the translational force component of a desired n -th node floor reaction force. Further, $F_{totalref}$ denotes the translational force component of a desired total floor reaction force (= desired 1423rd node floor reaction force). As shown in Fig. 8 mentioned above, a desired n -th node floor reaction force of an arbitrary n -th node ($n=14,23,1423$), which is not a leaf node, is determined by the resultant force of the desired node floor reaction forces of all child nodes of the n -th node. Therefore, $F_{14ref}=F_{1ref}+F_{4ref}$, $F_{23ref}=F_{2ref}+F_{3ref}$, and $F_{totalref}(=F_{1423ref})=F_{14ref}+F_{23ref}$. The hierarchical compliance operation determiner 114 determines the translational force components $F_{14ref}(=F_{1ref}+F_{4ref})$ and $F_{23ref}(=F_{2ref}+F_{3ref})$ of the desired node floor reaction forces of intermediate nodes, as described above, from the translational force components $F_{n_ref}(n=1,2,3,4)$ of the desired node floor reaction forces of the leaf nodes (the ground contact portion 10) determined by the desired floor reaction force distributor 102. $F_{totalref}(=F_{1423ref})$ is set to the translational force component of the desired total floor reaction force determined by the gait generating device 100.

Furthermore, the hierarchical compliance operation determiner 114 determines the moment component of a desired node floor reaction force of each node, excluding leaf nodes, having a desired node floor reaction force

central point being the point of action, as in the case of the translational force component of a desired node floor reaction force. In this case, however, according to the definition of a desired node floor reaction force central point Q_n ($n=1,2,3,4,14,23$), the moment horizontal component of a desired n -th node floor reaction force is always set to zero. The moment horizontal component of a desired 1423rd node floor reaction force (= desired total floor reaction force) is also set to zero.

In the robot 1 of the present embodiment, the ground contact portions 10 are engaged with the spherical joints 12 (free joints) at the distal end portions of the legs #1 to #4, so that floor reaction force moments (horizontal components and vertical components) cannot be generated in the ground contact portions 10 (leaf nodes). For this reason, in the hierarchical compliance operation determiner 114, the moment vertical components of the desired node floor reaction forces of the ground contact portions 10 (leaf nodes) are also set to zero.

If a desired node floor reaction force moment vertical component of a node that is not a leaf node is determined so as to dynamically balance with a desired motion of the robot 1, then it could generally take a non-zero value; however, in the present embodiment, the control related to the rotation (the rotation in the yaw direction) of the posture of the robot 1 about the vertical axis is not carried out. In the present

embodiment, therefore, the setting of the vertical component of the moment of a desired node floor reaction force of a node that is not a leaf node will be omitted. For this reason, the moment components of desired node floor reaction forces in the state shown in Fig. 3(b) will not be shown. If the control related to the rotation of the posture of the robot 1 about the vertical axis is carried out, then the desired floor reaction force moment vertical components of the nodes should be also set.

Supplementally, if the translational force components and the moment components of the desired node floor reaction forces of the nodes, including leaf nodes are determined by the desired floor reaction force distributor 102, then the determination need not be performed by the hierarchical compliance operation determiner 114.

Further, the hierarchical compliance operation determiner 114 also determines the translational force component and the moment component of an actual node floor reaction force, which is the actual floor reaction force of each node.

The translational force components of the actual floor reaction forces of the nodes (actual node floor reaction forces) in the state shown in Fig. 3(b) are illustratively shown in Fig. 11. In the diagram, a vector F_{n_act} ($n=1,2,3,4,14,23$) denotes a translational force component of an actual n -th node floor reaction force.

Further, $F_{totalact}$ denotes the translational force component of an actual total floor reaction force (= actual 1423rd node floor reaction force). In general, the translational force component of the actual floor reaction force of each node that is not a leaf node is the resultant force of the translational force components of the actual floor reaction forces of all child nodes of the node. Accordingly, the translational force components of the actual floor reaction forces of the 14th node, the 23rd node, and the 1423rd node are $F_{14act}=F_{1act}+F_{4act}$, $F_{23act}=F_{2act}+F_{3act}$, $F_{totalact}(=F_{1423act})=F_{14act}+F_{23act}$. The translational force components F_{1act} , F_{2act} , F_{3act} and F_{4act} of the actual floor reaction forces of the leaf nodes are the translational force components of the actual floor reaction forces (actual ground contact portion floor reaction forces) of the ground contact portions 10 obtained by the actual floor reaction force detector 108. The vectors shown by dashed lines in Fig. 11 indicate the translational force components of the desired node floor reaction forces shown in Fig. 10 mentioned above. The hierarchical compliance operation determiner 114 determines the translational force components of the actual node floor reaction forces of the nodes from the actual floor reaction forces of the ground contact portions 10 obtained by the actual floor reaction force detector 108.

The moment components of the actual floor reaction

forces of the nodes in the state shown in Fig. 3(b) are illustratively shown in Fig. 12. In the diagram, a vector Mn_act ($n=14,23,1423$) denotes the moment component of an actual n -th node floor reaction force. In this case, as
5 with the translational force components of the actual floor reaction forces of the nodes, in general, the moment component of an actual floor reaction force $M14act$, $M23act$ or $M1423act$ ($=Mtotalact$) of a node that is not a leaf node is defined as the moment component of the resultant force
10 of the actual floor reaction forces of all child nodes of the node (the moment component having the desired floor reaction force central point $Q14$, $Q23$ or $Q1423$ of the node as the point of action).

In the robot 1 of the present embodiment, no floor
15 reaction force moment can be generated in the ground contact portions 10 (leaf nodes), as described above, so that the moment components of the actual floor reaction forces of leaf nodes (actual ground contact portion floor reaction forces) will be always zero. Thus, the moment
20 components of the actual node floor reaction forces of the leaf nodes will not be shown.

The actual floor reaction force moment components of nodes that are not leaf nodes (in the present embodiment, $M14act$, $M23act$ and $M1423act$) are not generally zero. For
25 example, a moment is usually generated about the desired 14th node floor reaction force central point $Q14$ by the horizontal components of the translational force

components of the actual floor reaction forces of the first ground contact portion 10 (the 1st node) and the fourth ground contact portion 10 (the 4th node). However, in the robot 1 in the present embodiment, the distal end portions of the legs are provided with the spherical joints 12, which are free joints, so that a component in the same direction as a segment Q1Q4 of M14act and a component in the same direction as a segment Q2Q3 of M23act will be zero.

In a robot having the distal joints of its legs provided with actuators (a robot in which the postures of the distal ground contact portions of the legs are controllable), even if the control related to the rotation of the posture of the robot about the vertical axis is not carried out, the desired floor reaction force moment horizontal components of the ground contact portions are also set and the actual floor reaction force moments of the ground contact portions are also detected, as shown in an embodiment disclosed in Japanese Unexamined Patent Application Publication No. H10-277969 previously proposed by the present applicant. Then, an operation for correcting the postures of the ground contact portions should be performed so as to approximate the actual floor reaction force moment horizontal component of each ground contact portion to a desired floor reaction force moment horizontal component or to approximate the actual floor reaction force moment of each ground contact portion to

the sum (the vector sum) of the desired floor reaction force moment horizontal component and its ground contact portion compensating floor reaction force moment.

The processing of the hierarchical compliance operation determiner 114 will be explained in more detail. In this case, a situation is assumed in which the posture of the body 24 of the robot 1 is about to fall toward left rear in the state shown in Fig. 3(b) and the compensating total floor reaction force moment M_{dmd} determined by the posture stabilization control calculator 104 is as shown in Fig. 13.

To restore the posture (the inclination relative to the vertical direction) of the body 24 of the robot 1 (to restore the inclination in a desired body posture), the horizontal component of an actual total floor reaction force moment about a desired total floor reaction force central point (a desired ZMP) may be made to follow the horizontal component of the sum of a desired total floor reaction force moment $M_{totalref}$ ($=M_{1423ref}$) and a compensating total floor reaction force moment M_{dmd} .

Meanwhile, at the desired total floor reaction force central point (the desired ZMP), the horizontal component of the desired total floor reaction force moment $M_{totalref}$ is zero. Hence, to restore the posture (inclination) of the body 24 of the robot 1 in the longitudinal and lateral directions, the horizontal component of the actual total floor reaction force moment about the desired total floor

reaction force central point (the desired ZMP) may be made to follow the horizontal components (M_{dmdx} , M_{dmdy}) of M_{dmd} . Further, in the present embodiment, the actual floor reaction force moment about the desired floor reaction force central point of each ground contact portion 10 is zero.

Therefore, the hierarchical compliance operation determiner 114 in the first embodiment corrects the desired ground contact portion position (especially the position in the height direction) of each ground contact portion 10 determined by the gait generating device 100 so as to satisfy the aforesaid requirements 1) and 2) as much as possible.

To make the correction, the hierarchical compliance operation determiner 114 determines a compensating angle. The compensating angle is a manipulated variable (a rotational amount) for correcting the relative relationship among the positions of the ground contact portions 10 by the operation of rotation about a certain point (correcting in the vertical direction in the present embodiment). In the present embodiment, there are a 14th node compensating angle θ_{14} , a 23rd node compensating angle θ_{23} , and a 1423rd node compensating angle θ_{1423} as the compensating angles. In other words, they are the compensating angles of the nodes other than leaf nodes. Then, the hierarchical compliance operation determiner 114 determines a desired n-th node floor reaction force

central point Q_n' obtained by correcting the desired n-th node floor reaction force central point Q_n ($n=1,2,3,4,14,23$) on the basis of these compensating angles θ_{14} , θ_{23} and θ_{1423} .

5 As shown in Fig. 15, the 14th node compensating angle θ_{14} is the angle formed by a segment Q_1Q_4 and a segment $Q_1'Q_4'$, and the 23rd node compensating angle θ_{23} is the angle formed by a segment Q_2Q_3 and a segment $Q_2'Q_3'$. Further, as shown in Fig. 16, the 1423rd node compensating
10 angle θ_{1423} is the angle formed by a segment $Q_{14}Q_{23}$ and a segment $Q_{14}'Q_{23}'$. The technique for determining these node compensating angles θ_{14} , θ_{23} and θ_{1423} will be described later.

Referring to Fig. 15 and Fig. 16, the correction of
15 the desired n-th node floor reaction force central point Q_n ($n=1,2,3,4,14,23$) on the basis of the compensating angles θ_{14} , θ_{23} and θ_{1423} is made as follows.

Referring to Fig. 15, a normal vector V_{14} of a plane that includes a desired first node floor reaction force
20 central point Q_1 (the desired floor reaction force central point of a first ground contact portion 10) and a desired fourth node floor reaction force central point Q_4 (the desired floor reaction force central point of a second ground contact portion 10) and that is perpendicular to a
25 horizontal plane is determined. The magnitude of V_{14} is 1. The coordinate (position) of the desired first node floor reaction force central point Q_1 is rotationally moved

about a normal vector V_{14} with the desired 14th node floor reaction force central point Q_{14} as the center of rotation (about the axis that passes Q_{14} and is parallel to V_{14}) by the aforesaid 14th node compensating angle θ_{14} . The point after Q_1 is moved by the above rotational movement is defined as Q_1' . Similarly, the coordinate (position) of the desired fourth node floor reaction force central point Q_4 is rotationally moved about the normal vector V_{14} with the desired 14th node floor reaction force central point as the center of rotation by the 14th node compensating angle θ_{14} . The point after Q_4 is moved by the above rotational movement is defined as Q_4' . In other words, the ends of a segment obtained by rotating the segment Q_1Q_4 about V_{14} by θ_{14} with Q_{14} , which is an internally dividing point thereof, as the center of rotation are defined as Q_1' and Q_4' . Thus, the 14th node compensating angle θ_{14} is a manipulated variable for moving the relative relationship of the positions of the desired floor reaction force central points Q_1 and Q_4 of the first node and the fourth node, respectively, which are child nodes of the 14th node, without moving the position of the desired floor reaction force central point Q_{14} of the 14th node.

Moreover, a normal vector V_{23} of a plane that includes a desired second node floor reaction force central point Q_2 and a desired third node floor reaction force central point Q_3 and that is perpendicular to a

horizontal plane is determined. The magnitude of V_{23} is 1. The coordinate (position) of the desired second node floor reaction force central point Q_2 is rotationally moved about the normal vector V_{23} with the desired 23rd node floor reaction force central point Q_{23} as the center of rotation (about the axis that passes Q_{23} and is parallel to V_{23}) by the 23rd node compensating angle θ_{23} . As shown in Fig. 15, the point after Q_2 is moved by the above rotational movement is defined as Q_2' . Similarly, the coordinate (position) of the desired third ground contact portion floor reaction force central point Q_3 is rotationally moved about the normal vector V_{23} with the desired 23rd node floor reaction force central point as the center of rotation by the 23rd node compensating angle θ_{23} . The point after Q_3 is moved by the above rotational movement is defined as Q_3' . In other words, the ends of a segment obtained by rotating the segment Q_2Q_3 about V_{23} by θ_{23} with Q_{23} , which is an internally dividing point thereof, as the center of rotation are defined as Q_2' and Q_3' . Thus, the 23rd node compensating angle θ_{23} is a manipulated variable for moving the relative relationship of the positions of the desired floor reaction force central points Q_2 and Q_3 of the second node and the third node, respectively, which are child nodes of the 23rd node, without moving the position of the desired floor reaction force central point Q_{23} of the 23rd node.

Next, referring to Fig. 16, a normal vector V_{1423} of

a plane that includes a desired 14th node floor reaction force central point Q14 and a desired 23rd node floor reaction force central point Q23 and that is perpendicular to a horizontal plane is determined. The magnitude of V1423 is 1. The coordinate (position) of the desired 14th node floor reaction force central point Q14 is rotationally moved about the normal vector V1423 with the desired total floor reaction force central point P (=Q1423) as the center of rotation (about the axis that passes P and is parallel to V1423) by the 1423rd compensating angle θ_{1423} . The point after Q14 is moved by the above rotational movement is defined as Q14'. Similarly, the coordinate (position) of the desired 23rd ground contact portion floor reaction force central point Q23 is rotationally moved about the normal vector V1423 with the desired total floor reaction force central point P as the center of rotation by the 1423rd compensating angle θ_{1423} . The point after Q23 is moved by the above rotational movement is defined as Q23'. In other words, the ends of a segment obtained by rotating a segment Q14Q23 about V1423 by θ_{1423} with P(=Q1423), which is an internally dividing point thereof, as the center of rotation are defined as Q14' and Q23'. Thus, the 1423rd node compensating angle θ_{1423} is a manipulated variable for moving the relative relationship of the positions of the desired floor reaction force central points Q14 and Q23 of the 14th node and the 23rd node, respectively,

which are child nodes of the 1423rd node, without moving the position of the desired floor reaction force central point P of the 1423rd node.

Hereinafter, generally, a vector whose start point is A and end point is B will be denoted as a vector A_B .

Next, a point $Q1''$ that would be obtained when $Q1'$ is moved for a vector $Q14_Q14'$ is determined. Similarly, a point $Q4''$ that would be obtained when $Q4'$ is moved for a vector $Q14_Q14'$ is determined. Further, a point $Q2''$ that would be obtained when $Q2'$ is moved for a vector $Q23_Q23'$ is determined. Similarly, a point $Q3''$ that would be obtained when $Q3'$ is moved for a vector $Q23_Q23'$ is determined.

Subsequently, the desired ground contact portion position of an n-th ground contact portion ($n=1,2,3,4$) is moved in parallel by a vector Qn_Qn'' (substantially vertical movement). This corrects the desired ground contact portion position of each ground contact portion 10. Supplementally, as with the desired floor reaction force central point of each node, if the position of each leaf node is set to the position of the ground contact portion 10 corresponding to the leaf node, and the position of each node having child nodes is defined as a weighted average position of the positions of all child nodes of the node, using the weights set as described above, then the processing for moving the desired floor reaction force central points of the child nodes of the 14th node, the

23rd node and the 1423rd node, respectively, according to the compensating angles θ_{14} , θ_{23} and θ_{1423} , as described above, is equivalent to moving the positions of the child nodes of the 14th node, the 23rd node and the 1423rd node, respectively, according to the compensating angles θ_{14} , θ_{23} and θ_{1423} .

In a robot in which the distal end portions of its legs have no free joints (a robot in which the postures of ground contact portions can be controlled), the aforesaid parallel movement is performed without changing the postures (desired postures) of ground contact portions, and then the n-th ground contact portion is further rotated by a certain rotational angle θ_{n_x} about a longitudinal axis (X axis) and also rotated about a lateral axis (Y axis) by a certain rotational angle θ_{n_y} , with Q_n being the center. This corrects the desired postures of ground contact portions. The rotational angle θ_n (a two-dimensional amount composed of θ_{n_x} and θ_{n_y}) in this case is referred to as an n-th ground contact portion compensating angle, θ_{n_x} is referred to as an n-th ground contact portion compensating angle X component and θ_{n_y} is referred to as an n-th ground contact portion compensating angle Y component. The n-th ground contact portion compensating angle θ_n may be determined according to the technique described in Japanese Unexamined Patent Application Publication No. H10-277969 previously proposed by the present applicant.

Supplementally, each of the node compensating angles is determined such that a resultant force of a desired floor reaction force moment (the horizontal component thereof is zero) and a node compensating floor reaction force moment Mn_dmd is generated at the desired node floor reaction force central point of the node, which is the point of action. In this case, the compensating total floor reaction force moment $Mdmd$, which provides the basis of the node compensating floor reaction force moment Mn_dmd , is determined so as to approximate an actual posture inclination error to zero. Hence, each node compensating angle will function as a manipulated variable for manipulating the relative positional relationship among the ground contact portions 10 so as to approximate an actual posture inclination error to zero while approximating a floor reaction force moment about a desired total floor reaction force central point to a desired moment (a compensating total floor reaction force moment in this case).

As described above, the processing for correcting the desired ground contact portion positions (specifically, the mutual relative relationship among the positions) of the ground contact portions 10 is the hierarchical compliance operation in the first embodiment. In the compliance operation, for each node having child nodes, the manipulated variable (correction amount) of the relative relationship among the desired ground contact

portion positions (relative positional relationship) of the ground contact portions 10, which are the descendant nodes of the node, is established for each of the compensating angles θ_{14} , θ_{23} and θ_{1423} , and the

5 manipulated variables (correction amounts) are combined so as to correct the mutual relative relationship of the desired ground contact portion positions of the ground contact portions 10. The desired ground contact portion position/posture corrected as described above is referred to as a corrected desired ground contact portion position/posture.

10 In such a compliance operation, generally, if the aforesaid compensating angles (compensating operation amounts) are not excessive, then the ground contact region (a region of the ground contact surface wherein the pressure is positive) remains unchanged even if the ground contact pressure distribution of each ground contact portion 10 changes. In this case, the compliance mechanism 42 attached to each ground contact portion 10 deforms in proportion to a compensating angle, and an actual floor reaction force of each ground contact portion 10 based on the amount of the deformation is generated. As a result, the relationship between the compensating angles and the changing amounts of the actual floor reaction forces generated by the compensating angles has good characteristics, namely, linear characteristics, shown below.

Characteristic 1) If only the compensating angles about the desired floor reaction force central points of nodes that are not leaf nodes are manipulated to move the
5 desired ground contact portion positions of the ground contact portions 10, then the translational force components of the actual floor reaction forces of the ground contact portions 10 that have been lowered increase, while the translational force components of the actual
10 floor reaction forces of the ground contact portions 10 that have been raised decrease. At this time, the actual floor reaction force moments about the corrected desired floor reaction force central point of the ground contact portions 10 (leaf nodes) hardly change.

15 Characteristic 2) If only an n-th ground contact portion compensating angle is manipulated to rotate the desired posture of the n-th ground contact portion, then the moment component of the actual floor reaction force acting on the desired floor reaction force central point of the
20 n-th ground contact portion changes, while the translational force component does not change much.

Characteristic 3) If the compensating angle about the desired floor reaction force central point of a node that is not a leaf node and an n-th ground contact portion
25 compensating angle are simultaneously manipulated, then the change amount of the actual floor reaction forces of the ground contact portions 10 will be equivalent to the

sum of the change amount observed when each of them is independently manipulated.

Fig. 17 is a block diagram showing the functions of the hierarchical compliance operation determiner 114 in the present embodiment. Referring to the diagram, the processing of the hierarchical compliance operation determiner 114 will be explained in further detail.

The hierarchical compliance operation determiner 114 is equipped with, as its functional means, a compensating total floor reaction force moment distributor 114a, compensating angle determiners 114b, 114c and 114d, a corrected desired ground contact portion position/posture calculator 114g, a deformation compensation amount calculator 114n, and a corrected desired ground contact portion position/posture with deformation compensation calculator 114h.

The compensating total floor reaction force moment distributor 114a distributes the aforesaid compensating total floor reaction force moment M_{dmd} (M_{dmdx} , M_{dmdy}) to the 1423rd node compensating floor reaction force moment $M_{1423dmd}$, the 14th node compensating floor reaction force moment M_{14dmd} and the 23rd node compensating floor reaction force moment M_{23dmd} .

The 1423rd node compensating floor reaction force moment $M_{1423dmd}$ is the desired value of a moment to be generated about the desired 1423rd node floor reaction force central point (= desired total floor reaction force

central point (desired ZMP)) by the translational force components of the floor reaction forces of the ground contact portions 10 (specifically, the first to the fourth ground contact portions) when the 1423rd compensating angle θ_{1423} is manipulated.

The component of the 1423rd node compensating floor reaction force moment $M_{1423dmd}$ in the direction of the aforesaid vector V_{1423} (the component about the axis in the V_{1423} direction) is described as $M_{1423dmdv}$. The vector V_{1423} is the vector defined in the general explanation of the compliance operation of the hierarchical compliance operation determiner 114 (refer to Fig. 16). If a vector orthogonal to V_{1423} and also orthogonal to the vertical direction is defined as U_{1423} , then the component in the direction of U_{1423} of the 1423rd node compensating floor reaction force moment $M_{1423dmd}$ (the component about the axis in the U_{1423} direction) $M_{1423dmdu}$ is set to zero in the present embodiment. This is because the component of a floor reaction force moment in the U_{1423} direction cannot be generated even if the 1423rd node compensating angle θ_{1423} is manipulated in the robot 1 of the present embodiment. Further, in the present embodiment, the rotation of the posture of the robot 1 about the vertical axis is not controlled; therefore, the component $M_{1423dmdz}$ of $M_{1423dmd}$ in the vertical direction is also set to zero.

The 14th node compensating floor reaction force

moment M_{14dmd} is the desired value of a moment to be generated about the desired 14th node floor reaction force central point by the translational force components of the floor reaction forces of the ground contact portions 10 (specifically, the first and the fourth ground contact portions) when the 14th compensating angle θ_{14} is manipulated.

The component of the 14th node compensating floor reaction force moment M_{14dmd} in the direction of the vector V_{14} is described as M_{14dmdv} . The vector V_{14} is the vector defined in the general explanation of the compliance operation of the hierarchical compliance operation determiner 114 (refer to Fig. 15). If a vector orthogonal to V_{14} and also orthogonal to the vertical direction is defined as U_{14} , then the component M_{14dmdu} in the direction of U_{14} of the 14th node compensating floor reaction force moment M_{14dmd} is set to zero in the present embodiment. This is because the component of a floor reaction force moment in the U_{14} direction cannot be generated even if the 14th node compensating angle θ_{14} is manipulated in the robot 1 of the present embodiment. In the present embodiment, the component of M_{14dmd} in the vertical direction is also set to zero.

The 23rd node compensating floor reaction force moment M_{23dmd} is the desired value of a moment to be generated about the desired 23rd node floor reaction force central point by the translational force components of the

floor reaction forces of the ground contact portions 10 (specifically, the second and the third ground contact portions) when the 23rd compensating angle θ_{23} is manipulated.

5 The component of the 23rd node compensating floor reaction force moment M_{23dmd} in the direction of the vector V_{23} is described as M_{23dmdv} . The vector V_{23} is the vector defined in the general explanation of the compliance operation of the hierarchical compliance operation determiner 114 (refer to Fig. 15). If a vector
10 orthogonal to V_{23} and also orthogonal to the vertical direction is defined as U_{23} , then the component M_{23dmdu} in the direction of U_{23} of the 23rd node compensating floor reaction force moment M_{23dmd} is set to zero in the present
15 embodiment. This is because the component of a floor reaction force moment in the U_{23} direction cannot be generated even if the 23rd node compensating angle θ_{23} is manipulated in the robot 1 of the present embodiment. In the present embodiment, the component of M_{23dmd} in the
20 vertical direction is also set to zero.

 The 1423rd node compensating floor reaction force moment $M_{1423dmd}$, the 14th node compensating floor reaction force moment M_{14dmd} and the 23rd node compensating floor reaction force moment M_{23dmd} are determined, for example,
25 as follows.

 On an arbitrary n-th node, when a desired n-th node floor reaction force central point has been corrected

while maintaining the horizontal component of an n-th node compensating floor reaction force moment at zero so as to be equivalent to adding the n-th node compensating floor reaction force moment to the desired n-th node floor reaction force central point, the desired n-th node floor reaction force central point position that has been corrected is referred to as a corrected desired n-th node floor reaction force central point position.

The relationships between a corrected desired 1423rd node floor reaction force central point P_{mdfd} ($=Q_{1423mdfd}$), a corrected desired 14th node floor reaction force central point Q_{14mdfd} , and a corrected desired 23rd node floor reaction force central point Q_{23mdfd} , and node compensating floor reaction force moments are shown in the following expressions 7 to 9. The desired 1423rd node floor reaction force central point Q_{1423} agrees with the total floor reaction force central point P , so that the corrected desired 1423rd node floor reaction force central point P_{mdfd} may be referred to as a corrected desired total floor reaction force central point in some cases.

$$M_{1423dmd} = (P_{mdfd} - P) * F_{totalref} \quad \dots \text{Expression 7}$$

$$M_{14dmd} = (Q_{14mdfd} - Q_{14}) * F_{14ref} \quad \dots \text{Expression 8}$$

$$M_{23dmd} = (Q_{23mdfd} - Q_{23}) * F_{23ref} \quad \dots \text{Expression 9}$$

The difference between two points, such as $(P_{mdfd} - P)$ in expression 7, means the difference in the positional

vectors of the points. Further, $F_{totalref}$, F_{14ref} and F_{23ref} denote the translational force components of the desired node floor reaction forces of the 1423rd node, the 14th node and the 23rd node, respectively, as shown in Fig. 10.

To maintain high ground contact properties of the robot 1, control should not be carried out to bring the floor reaction force of the ground contact portion 10 to be in contact with the ground excessively close to zero or a negative value. Hence, the following conditions 1) to 3) should be satisfied.

Corrected node existing position condition 1)

P_{mdfd} is not excessively close to an end of the segment $Q_{14}Q_{23}$ from the total floor reaction force central point P and exists on the segment $Q_{14}Q_{23}$. The range in which the corrected desired 1423rd node floor reaction force central point (corrected desired total floor reaction force central point) P_{mdfd} should exist is referred to as the existence permissible range of the corrected desired 1423rd node floor reaction force central point (corrected desired total floor reaction force central point).

Corrected node existing position condition 2)

Q_{14mdfd} is not excessively close to an end of the segment $Q_{14}Q_4$ from the desired 14th node floor reaction force central point Q_{14} and exists on the segment $Q_{14}Q_4$. The range in which the corrected desired 14th node floor

reaction force central point Q_{14mdfd} should exist is referred to as the existence permissible range of the corrected desired 14th node floor reaction force central point.

5 Corrected node existing position condition 3)

Q_{23mdfd} is not excessively close to an end of the segment Q_2Q_3 from the desired 23rd node floor reaction force central point Q_{23} and exists on the segment Q_2Q_3 . The range in which the corrected desired 23rd node floor
10 reaction force central point Q_{23mdfd} should exist is referred to as the existence permissible range of the corrected desired 23rd node floor reaction force central point.

15 Meanwhile, to obtain an appropriate posture restoring force actually generated in the robot 1 (the force for restoring the inclination of the body 24 to a desired body posture inclination), the resultant force of the 1423rd node compensating floor reaction force moment
20 $M_{1423dmd}$, the 14th node compensating floor reaction force moment M_{14dmd} and the 23rd node compensating floor reaction force moment M_{23dmd} should approximately agree with the compensating total floor reaction force moment M_{dmd} . In other words, the following expression 10 should
25 be approximately satisfied.

$$M_{dmd} = M_{1423dmd} + M_{14dmd} + M_{23dmd} \quad \dots \text{Expression 10}$$

In the present embodiment, therefore, the 1423rd node compensating floor reaction force moment $M_{1423dmd}$, the 14th node compensating floor reaction force moment M_{14dmd} and the 23rd node compensating floor reaction force moment M_{23dmd} are determined according to expressions 11 to 13 given below as long as the positions of the corrected desired node floor reaction force central points P_{mdfd} , Q_{14mdfd} and Q_{23mdfd} determined by the above and the aforesaid expression 7, expression 8 and expression 9 satisfy the aforesaid corrected node existence position conditions 1), 2) and 3).

$$M_{1423dmd} = Mat_{1423} * Mdmd * V_{1423} \quad \dots \text{Expression 11}$$

$$M_{14dmd} = Mat_{14} * Mdmd * V_{14} \quad \dots \text{Expression 12}$$

$$M_{23dmd} = Mat_{23} * Mdmd * V_{23} \quad \dots \text{Expression 13}$$

where Mat_{1423} , Mat_{14} and Mat_{23} denote gain matrixes (1-row, 3-column matrixes with a third element being zero), and these are set such that $M_{1423dmd}$, M_{14dmd} and M_{23dmd} determined according to expression 11, expression 12 and expression 13 satisfy expression 10.

More precisely, the gain matrixes Mat_{1423} , Mat_{14} and Mat_{23} are determined such that a simultaneous equation composed of expression 10, expression 11, expression 12 and expression 13 identically holds regardless of the value of $Mdmd$. The gain matrix for the simultaneous

equation to identically hold is not uniquely determined,
so that an appropriate gain matrix may be determined
depending on, for example, which one of the corrected node
existence position conditions 1), 2) and 3) is especially
5 important. Supplementally, the gain matrixes are
desirably changed continuously in order to continuously
change the compensating angles θ_{1423} , θ_{14} and θ_{23} . Further,
the policy of setting gain matrixes may be changed
according to whether the robot 1 is standing upright or
10 the difference in movement mode or the like.

If the 1423rd node compensating floor reaction force
moment $M_{1423dmd}$, the 14th node compensating floor reaction
force moment M_{14dmd} and the 23rd node compensating floor
reaction force moment M_{23dmd} determined according to
15 expression 11, expression 12 and expression 13 do not
satisfy any one of the corrected node existence position
conditions 1), 2) and 3), then they are to be corrected to
satisfy the conditions 1), 2) and 3). More specifically,
of the corrected desired n-th node floor reaction force
20 central points ($n=1423, 14, 23$), the corrected desired node
floor reaction force central point that has exceeded the
existence permissible range is set on the boundary of the
existence permissible range, and the remaining corrected
desired node floor reaction force central points are
25 determined so as to satisfy expression 11, expression 12
and expression 13 as much as possible (to minimize the
absolute value of the difference between a left side and a

right side as much as possible). Generally, however, the behavior of a controlled object does not considerably change even if a feedback amount slightly changes in feedback control; therefore, it is not required to strictly or forcibly satisfy expression 11, expression 12 and expression 13.

Thus, the compensating total floor reaction force moment distributor 114a determines the node compensating floor reaction force moments $M_{1423dmd}$, M_{14dmd} and M_{23dmd} . Fig. 14 shows the examples of the node compensating floor reaction force moments $M_{1423dmd}$, M_{14dmd} and M_{23dmd} determined as described above. In the figure, M_{dmd} is the same as that shown in Fig. 13 mentioned above.

Moreover, the compensating total floor reaction force moment distributor 114a determines the corrected desired ground contact portion floor reaction forces $F_{n_refmdfd}$ ($n=1,2,3,4$), which are the desired floor reaction forces of the ground contact portions 10 that are corrected by adding node compensating floor reaction force moments to desired ground contact portion floor reaction forces, on the basis of the desired ground contact portion floor reaction forces, which are the desired floor reaction forces of the ground contact portions 10 (the desired node floor reaction forces of leaf nodes) and the node compensating floor reaction force moments $M_{1423dmd}$, M_{14dmd} and M_{23dmd} .

At this time, the corrected desired ground contact

portion floor reaction forces $F_{n_refmdfd}$ ($n=1,2,3,4$) may be determined from the desired floor reaction force central points Q_n ($n=1,2,3,4$), the corrected total floor reaction force central points P_{mdfd} , the corrected desired node floor reaction force central points Q_{14mdfd} and Q_{23mdfd} , and the desired total floor reaction forces $F_{totalref}$ of the ground contact portions 10 by the same technique as the technique for determining deciding desired node floor reaction forces from the desired floor reaction force central points (the desired node floor reaction force central points of leaf nodes) Q_n ($n=1,2,3,4$), the desired total floor reaction force central points P , the desired node floor reaction force central points Q_{14} and Q_{23} , and the desired total floor reaction forces $F_{totalref}$ of the ground contact portions 10. In other words, the weights of the nodes are determined according to the aforesaid expressions 1 to 3 from the desired floor reaction force central points Q_n ($n=1,2,3,4$), the corrected total floor reaction force central points P_{mdfd} , the corrected desired node floor reaction force central points Q_{14mdfd} and Q_{23mdfd} of the ground contact portions 10, and the corrected desired ground contact portion floor reaction forces $F_{n_refmdfd}$ ($n=1,2,3,4$) may be determined according to the aforesaid expression 4 by using the determined weight.

As is obvious from the above, generating a node compensating floor reaction force moment at a desired n -th

node floor reaction force central point of an n-th node having child nodes (correcting the moment component of the desired floor reaction force acting on a desired n-th node floor reaction force central point) is equivalent to
5 correcting the weights of the child nodes of the n-th node.

The processing of the compensating total floor reaction force moment distributor 114a explained above is represented by the functional block diagram shown in Fig. 18. More specifically, based on the desired node floor
10 reaction force central points $Q_n(n=1,2,3,4,14,23)$, the existence permissible ranges of the 14th node, the 23rd node and the corrected desired node floor reaction force central points $Q_n_mdfd(n=14,23,1423)$ are determined according to the aforesaid corrected node existence
15 position conditions 1), 2) and 3). Further, the corrected desired node floor reaction force central points $Q_n_mdfd(n=14,23,1423)$ and the node compensating floor reaction force moments $M_n_dmd(n=14,23,1423)$ are determined on the basis of the compensating total floor reaction force
20 moment M_{dmd} , the desired floor reaction force central points of nodes $Q_n(n=1,2,3,4,14,23,1423)$, the desired floor reaction forces $F_n_ref(n=1,2,3,4,14,23,1423)$ and the aforesaid existence permissible ranges. In addition, the corrected desired ground contact portion floor reaction
25 forces $F_n_refmdfd(n=1,2,3,4)$ are determined on the basis of the corrected desired node floor reaction force central points $Q_n_mdfd(n=14,23,1423)$, the desired floor reaction

force central points $Q_n(n=1,2,3,4)$ of the ground contact portions 10, and the desired total floor reaction force $F_{totalref}$.

Next, the processing of the compensating angle determiner (01423 determiner) 114b out of the aforesaid compensating angle determiners 114b to 114d will be explained with reference to the block diagram of Fig. 19. If the translational force component ($F_{1act}+F_{4act}$) of the resultant force of the actual first node floor reaction force and the actual fourth node floor reaction force acts on a desired 14th node floor reaction force central point Q_{14} and the translational force component ($F_{2act}+F_{3act}$) of the resultant force of the actual second node floor reaction force and the actual third node floor reaction force acts on a desired 23rd node floor reaction force central point Q_{23} , a moment $M_{1423act}$ generated about the desired total floor reaction force central point P (the desired 1423rd node floor reaction force central point) by the above translational force components is determined according to expression 14 given below.

$$M_{1423act} = P_{Q14} * (F_{1act} + F_{4act}) + P_{Q23} * (F_{2act} + F_{3act})$$

... Expression 14

where P_{Q14} denotes a vector whose start point is P and end point is Q_{14} , and P_{Q23} denotes a vector whose start point is P and end point is Q_{23} .

In actuality, there will be hardly a problem if expression 15 given below is used in place of expression 14 to calculate M1423act.

$$\begin{aligned} 5 \quad M1423act = & P_Q1*F1act + P_Q2*F2act \\ & + P_Q3*F3act + P_Q4*F4act \\ & \dots \text{Expression 15} \end{aligned}$$

The right side of expression 15 is an expression for
10 calculating the actual total floor reaction force moment
Mtotalact acting about the desired total floor reaction
force central point P from the translational force
components $F_{n_act}(n=1,2,3,4)$ of the actual floor reaction
forces of the first to the fourth nodes (leaf nodes).
15 Supplementally, in expression 14, the actual floor
reaction force moment acting about the desired 14th node
floor reaction force central point Q14 and the actual
floor reaction force moment acting about the desired 23rd
node floor reaction force central point Q23 are subtracted
20 from the actual total floor reaction force moment
Mtotalact acting about the desired total floor reaction
force central point P.

In general, an actual n-th node floor reaction force
moment M_{n_act} of an arbitrary n-th node, which is a leaf
25 node, is the actual floor reaction force moment of an n-th
ground contact portion. Regarding an arbitrary n-th node,
which is not a leaf node, the moment from the floor

reaction forces of all child nodes thereof acting on the
desired n-th node floor reaction force central point (the
floor reaction forces of the child nodes here are,
strictly speaking, the floor reaction forces acting on the
desired floor reaction force central points of the child
nodes) is referred to as an actual n-th node floor
reaction force moment M_{n_act} . As in expression 14 and
expression 15, there are two different definitions of an
actual n-th node floor reaction force moment. One
includes the actual floor reaction force moments of child
nodes and the other does not include them; however, either
of the definitions may be used. Especially when the
responsiveness of feedback control for controlling the
horizontal components of the actual floor reaction force
moments of child nodes is high, the horizontal components
of the actual floor reaction force moments of the child
nodes immediately converges to zero, so that the behavior
of the control of the actual floor reaction force of an n-
th node does not change much when either of the
definitions is used.

Expression 16 shown below is a general expression
for calculating an actual n-th node floor reaction force
moment corresponding to expression 14, and expression 17
is a general expression for calculating an actual n-th
node floor reaction force moment corresponding to
expression 15. In expression 16 and expression 17, $Q_n_Q_m$
is a vector whose start point is Q_n and end point is Q_m .

An actual floor reaction force moment M_{m_act} of an m -th node, which is a leaf node, is an actual floor reaction force moment of each ground contact portion detected by an actual floor reaction force detector.

5

when $m \in \{\text{set of numbers of child nodes of } n\text{-th node}\},$

$$M_{n_act} = \Sigma (Q_n \cdot Q_m \cdot F_{m_act}) \quad \dots \text{Expression 16}$$

when $m \in \{\text{set of numbers of leaf nodes, which are descendants of } n\text{-th node}\},$

10

$$M_{n_act} = \Sigma (Q_n \cdot Q_m \cdot F_{m_act} + M_{m_act}) \quad \dots \text{Expression 17}$$

Σ in expressions 16 and 17 means the total sum regarding m . Supplementally, in the first embodiment, the actual floor reaction force moment about the desired floor reaction force central point of a leaf node (each ground contact portion) becomes zero; therefore, the right side of the above expression 15 does not include a component of M_{m_act} of expression 17. In a robot in which the postures of ground contact portions can be controlled, M_{m_act} of expression 17 generally does not become zero.

15

20

The 1423rd node compensating angle θ_{1423} may generally be determined by feedback control law or the like such that the difference between $M_{1423act}$ determined as described above and the 1423rd node compensating floor reaction force moment $M_{1423dmd}$ previously determined by the compensating total floor reaction force moment

25

distributor 114a (M1423act-M1423dmd) is approximated to zero. For example, θ_{1423} may be determined by, for example, multiplying the difference by a predetermined gain matrix (tertiary diagonal matrix).

5 However, in the present embodiment, the 1423rd node compensating angle θ_{1423} about the axis in the direction of the aforesaid vector V1423 may be determined, so that θ_{1423} may be determined on the basis of the difference between a component M1423actv in the direction of the
10 vector V1423 of M1423act and a component M1423dmdv in the direction of the vector V1423 of M1423dmd. And, at this time, in the present embodiment, M1423actv and M1423dmdv are passed through a filter before determining θ_{1423} on the basis of the difference therebetween in order to
15 enhance the responsiveness and stability of the control of floor reaction forces.

 Specifically, the component M1423actv in the direction of the vector V1423 of M1423act determined as described above is extracted. This is obtained by the
20 following expression 18 using a scalar product calculation "\cdot" of a vector.

$$M1423actv = M1423act \cdot V1423 \quad \dots \text{Expression 18}$$

25 The processing for calculating M1423actv as described above is executed by a calculator indicated by a reference numeral 114k in Fig. 19.

Next, the aforesaid $M_{1423actv}$ is passed through a low-pass filter 114i to obtain $M_{1423actvfilt}$. Furthermore, the component $M_{1423dmdv}$ in the V_{1423} direction of the aforesaid 1423rd node compensating floor reaction force moment $M_{1423dmd}$ is passed through a compensating filter 114j to obtain $M_{1423dmdvfilt}$. Incidentally, $M_{1423dmdv}$ is determined by the scalar product calculation of $M_{1423dmd}$ and V_{1423} , as with the aforesaid expression 18. Then, the result obtained by subtracting $M_{1423dmdvfilt}$ from $M_{1423actvfilt}$ provides a component $M_{1423errv}$ in the direction of an error moment V_{1423} .

The aforesaid compensating filter 114j improves the frequency response characteristic of transfer functions from $M_{1423dmdv}$ to an actual total floor reaction force moment in a control device.

Lastly, the aforesaid 1423rd node compensating angle θ_{1423} is obtained by the calculation of the feedback control law (proportional control law in this case) of the following expression 19. Here, K_{1423} denotes a control gain, and it is normally set to a positive value.

$$\theta_{1423} = K_{1423} * M_{1423errv} \quad \dots \text{Expression 19}$$

This means that the component $M_{1423errv}$ in direction of the error moment V_{1423} is multiplied by the control gain K_{1423} to obtain the 1423rd node compensating angle θ_{1423} .

The processing of the compensating angle determiner

(014 determiner) 114c in Fig. 17 will now be explained with reference to Fig. 20. The translational force component F_{1act} of the actual first node floor reaction force (the actual floor reaction force of the first ground contact portion 10) acts on a desired first node floor reaction force central point Q_1 and the translational force component F_{4act} of the actual fourth node floor reaction force (the actual floor reaction force of the fourth ground contact portion 10) acts on a desired fourth node floor reaction force central point Q_4 , a moment M_{14act} generated about the desired 14th node floor reaction force central point Q_{14} by the above translational force components is determined according to the aforesaid expression 16, which is a general expression.

More specifically, it is determined according to the following expression 20.

$$M_{14act} = Q_{14_Q1} * F_{1act} + Q_{14_Q4} * F_{4act} \quad \dots \text{Expression 20}$$

where Q_{14_Q1} denotes a vector whose start point is Q_{14} and end point is Q_1 , and Q_{14_Q4} denotes a vector whose start point is Q_{14} and end point is Q_4 .

In actuality, for the reason described previously, there will be hardly a problem if the following expression 21 (expression substantiating the above expression 17) is used in place of expression 20.

$$M_{14act} = Q_{14_Q1} * F_{1act} + Q_{14_Q4} * F_{4act} + M_{1act} + M_{4act}$$

... Expression 21

where M_{1act} denotes an actual first node floor reaction
5 force moment and M_{4act} denotes an actual fourth node floor
reaction force moment. In the first embodiment, the
distal portions of the legs #1 to #4 are provided with
free joints (spherical joints 12), so that M_{1act} and M_{4act}
are zero.

10 Expression 21 is an expression for calculating the
moment acting about the desired 14th node floor reaction
force central point generated by the resultant force of
the actual floor reaction forces of all leaf nodes of the
14th node. Incidentally, expression 20 subtracts the
15 actual first node floor reaction force moment and the
actual fourth node floor reaction force moment from the
moment acting about the desired 14th floor reaction force
central point generated by the resultant force of the
actual floor reaction forces of all leaf nodes of the 14th
20 node.

The 14th node compensating angle θ_{14} may be
generally determined by the feedback control law or the
like so as to approximate the difference between M_{14act}
determined as described above and the 14th node
25 compensating floor reaction force moment $M_{1423dmd}$
previously determined by the compensating total floor
reaction force moment distributor 114a ($M_{14act} - M_{14dmd}$) to

zero.

In the present embodiment, however, for the same reason as that in the case of 01423, 014 is determined on the basis of the difference between the component M14actv of M14act in the aforesaid direction of the vector V14 and the component M14dmdv of M14dmd in the direction of the vector V14, which have been respectively passed through a filter.

More specifically, the component M14actv of M14act in the direction of the vector V14 determined as described above is extracted. This is obtained by expression 22 that uses the scalar product calculation of vectors.

$$M14actv = M14act \cdot V14 \quad \dots \text{Expression 22}$$

The processing for calculating M14actv as described above is carried out by a calculator indicated by a reference character 114k' in Fig. 20.

Next, the aforesaid M14actv is passed through a low-pass filter 114i' to obtain M14actvfilt. Further, the component M14dmdv of the aforesaid 14th node compensating floor reaction force moment in the direction of V14 is passed through a compensating filter 114j' to obtain M14dmdvfilt. Incidentally, M14dmdv is determined by the scalar product calculation of M14dmd and V14. Then, M14dmdvfilt is subtracted from M14actvfilt to obtain a component M14errv in the direction of an error moment V14.

Incidentally, the compensating filter 114j' improves the frequency response characteristics of transfer functions from M14dmdv to actual total floor reaction force moments in a control device.

5 Lastly, the aforesaid 14th node compensating angle θ_{14} is obtained by the calculation of the feedback control law (proportional control law in this case) of expression 23 given below. Here, K14 denotes a control gain, which is normally set to a positive value.

10
$$\theta_{14} = K_{14} * M_{14errv} \quad \dots \text{Expression 23}$$

 The processing of the compensating angle determiner (θ_{23} determiner) 114d in Fig. 17 is the same as the
15 processing of the 14th node compensating angle θ_{14} determiner 114c; therefore, detailed explanation thereof will be omitted here. The following provides an overview of the processing. A component M23actv of a moment M23act in the direction of a vector V23, the moment being
20 generated about a desired 23rd node floor reaction force central point Q23 by the actual floor reaction forces of the child nodes of a 23rd node, is calculated on the basis of the aforesaid expression 16 or 17. Then, the 23rd node compensating angle θ_{23} is calculated by the arithmetic
25 processing of the feedback control law (proportional control law) from a component M23errv in the direction of the error moment V23 obtained by subtracting M23actvfilt,

which is obtained by passing the above M_{23actv} through a low-pass filter, from $M_{23dmdvfilt}$ obtained by passing M_{23dmdv} of the aforesaid 23rd node compensating floor reaction force moment M_{23dmd} in the direction of V_{23} through a compensating filter.

The processing of the compensating angle determiners 114b to 114d determines the sets of the node compensating angles θ_{1423} , θ_{14} and θ_{23} such that the horizontal components of the actual moments M_{act} acting on the desired total floor reaction force central points P are approximated to the compensating total floor reaction force moment M_{dmd} . In the present embodiment, θ_{1423} has been determined by the aforesaid expression 19; alternatively, however, it may be determined on the basis of the difference between $M_{1423act}+M_{14act}+M_{23act}$ (the total sum of actual node floor reaction force moments) and $M_{1423dmd}$ or the difference between the total sum of actual node floor reaction force moments and $M_{1423dmd}$, which have been respectively passed through a filter, in place of $M_{1423err}$ of the right side of expression 19.

Supplementally, in the present embodiment, a node compensating floor reaction force moment has been determined without changing the desired node floor reaction force central point Q_n of each node, the Q_n being the point of action. Then, the difference between the node floor reaction force compensating moment (more precisely, the resultant force of the node compensating

floor reaction force moment and the moment component of the desired node floor reaction force having Q_n as its point of action) and an actual node floor reaction force moment having Q_n as its point of action has been used as a control amount to determine a node compensating angle such that the control amount is approximated to zero. Instead of determining the node compensating angles as described above, the node compensating angles θ_{1423} , θ_{14} and θ_{23} may be determined as follows. On each n-th node

($n=14, 23, 1423$) having child nodes, a floor reaction force central point that causes the horizontal component of the moment of the actual node floor reaction force of the n-th node (the resultant force of the actual node floor reaction forces of all child nodes of the n-th node) to become zero is determined as an actual n-th node floor reaction force central point. Alternatively, a floor reaction force central point that causes the horizontal component of a moment, which is obtained by subtracting the moment acting on the desired node floor reaction force central point of each child node due to the actual node floor reaction force of the child node from the moment of the actual node floor reaction force of an n-th node ($n=14, 23, 1423$), to become zero is determined as an actual n-th node floor reaction force central point. For example, the actual 14th node floor reaction force central point related to the 14th node is determined as a point obtained by shifting, on the segment Q_1Q_4 , the desired 14th node

floor reaction force central point by the value obtained
by dividing the horizontal component of M_{14act} determined
by the aforesaid expression 16 or 17 by the vertical
component of the resultant force of F_{1act} and F_{4act} (the
5 translational force component of an actual 14th node floor
reaction force). The same applies to the node floor
reaction force central points of the 23rd node and the
1423rd node. Then, the difference between the desired
node floor reaction force central point of an n-th node
10 (n=14,23,1423) and the actual n-th node floor reaction
force central point determined as described above, or the
difference between the values obtained by passing each of
the above node floor reaction force central points through
a filter is defined as a control amount, and the node
15 compensating angles θ_{1423} , θ_{14} and θ_{23} are determined on
the basis of the control amount such that the control
amount is approximated to zero (e.g., θ_{1423} , θ_{14} and θ_{23}
are determined by multiplying the control amount by a
certain gain).

20 The corrected desired ground contact portion
position/posture calculator 114g in Fig. 17 obtains
corrected desired ground contact portion position/posture
by correcting the desired ground contact portion
position/posture, which are the desired position and the
25 desired posture of each ground contact portion 10,
according to a technique for correcting the desired ground
contact portion position/posture of the aforesaid

hierarchical compliance operation (the technique explained with reference to Fig. 15 and Fig. 16) on the basis of the 1423rd node compensating angle θ_{1423} , the 14th node compensating angle θ_{14} , and the 23rd node compensating angle θ_{23} . However, in the present embodiment, the distal portions of the legs #1 to #4 are provided with free joints (spherical joints 12), and the posture of each ground contact portion 10 cannot be intentionally changed, so that the corrected desired ground contact portion position/posture actually means the corrected desired ground contact portion position.

Fig. 21 is a functional block diagram showing the processing of the aforesaid deformation compensation amount calculator 114n in Fig. 17. As shown in Fig. 21, the deformation compensation amount calculator 114n determines deformation amounts $E_{n_mdfd}(n=1,2,3,4)$, which are the deformation amounts of the legs #1 to #4 (the deformation amounts of the link mechanisms of the legs and the compliance mechanism 42), the deformation being expected to occur due to the corrected desired ground contact portion floor reaction forces $F_{n_refmdfd}(n=1,2,3,4)$ of the ground contact portions 10 that are output from the compensating total floor reaction force moment distributor 114a (the desired ground contact portion floor reaction forces that have been corrected by adding the 1423rd node compensating floor reaction force moment $M_{1423dmd}$, the 14th node compensating floor reaction

force moment M14dmd and the 23rd node compensating floor
reaction force moment M23dmd to desired ground contact
portion floor reaction forces). The deformation amounts
En_mdmd(n=1,2,3,4) are determined by using a mechanism
5 compliance model showing the relationship between the
forces (or floor reaction forces) acting on the legs and
the deformations of the legs. Then, the deformation
compensation amount calculator 114n determines deformation
compensation amounts En_cmpn(n=1,2,3,4) for canceling the
10 deformation amounts En_mdmd(n=1,2,3,4). The deformation
compensation amount En_cmpn is determined by multiplying
each deformation amount En_mdmd by (-1).

The corrected desired ground contact portion
position/posture with deformation compensation calculator
15 114h in Fig. 17 adds a further correction to the corrected
desired ground contact portion position/posture of each
ground contact portion 10 (the position/posture determined
by the aforesaid corrected desired ground contact portion
position/posture calculator 114g) so as to cancel the
20 calculated deformation amount En_mdmd, thereby obtaining
the corrected desired ground contact portion
position/posture with deformation compensation of each
ground contact portion 10. The corrected desired ground
contact portion positions/postures with deformation
25 compensation are determined by adding individually
corresponding deformation compensation amounts En_cmpn to
the corrected desired ground contact portion

position/posture of the ground contact portions 10.

For example, if it is calculated that a corrected desired ground contact portion floor reaction force causes the compliance mechanism 42 or the like of a leg

5 corresponding to a certain ground contact portion 10 to contract by z in the vertical direction, then the

corrected desired ground contact portion floor reaction force is corrected so as to lower the desired position of the ground contact portion 10 by z . More specifically,

10 the corrected desired ground contact portion

position/posture with deformation compensation is

calculated such that the position/posture when the ground contact surface (bottom surface) of the ground contact portion 10 after deformation compensation is deformed

15 under a desired ground contact portion floor reaction force agrees with the desired position/posture of the ground contact surface of the ground contact portion before the deformation compensation. Incidentally,

detailed explanation thereof is explained in detail in

20 Japanese Unexamined Patent Application Publication No.

H10-277969. In the robot 1 of the present embodiment, the postures of the ground contact portions 10 cannot be

controlled, so that the corrected desired ground contact portion position/posture with deformation compensation

25 calculator 114h actually corrects the corrected desired ground contact portion positions of the ground contact portions 10.

The deformation compensation described above is implemented by control for canceling in a feed-forward manner the shifts in actual ground contact portion position/posture caused by a deformation of the compliance mechanism 42 or the like. In comparison with a case where
5 no such control is carried out, it is possible to enable the robot 1 to travel in a gait that is further closer to a desired gait.

The above has given the details of the processing of
10 the hierarchical compliance operation determiner 114.

Based on the above, resuming the explanation of the flowchart in Fig. 9, compensating angles are determined as described above in S34. Fig. 22 is a flowchart showing a generalized subroutine of the processing for determining
15 the compensating angles.

To explain with reference to the figure, first, the translational force components

$F_{n_act}(n=1,2,3,4,14,23,1423)$ of actual n-th node floor reaction forces are calculated on the basis of the actual
20 floor reaction forces of the ground contact portions 10

(the actual floor reaction forces obtained by the aforesaid actual floor reaction force detector 108). In this case, the translational force components

$F_{n_act}(n=1,2,3,4)$ of the actual node floor reaction forces
25 of the leaf nodes are the translational force components of the detected values of the actual floor reaction forces of the ground contact portions 10 by the aforesaid actual

floor reaction force detector 108. Further, the translational force component $F_{n_act}(n=14,23,1423)$ of the actual node floor reaction force of a node that is not a leaf node is the translational force component of the resultant force of the actual node floor reaction forces of the child nodes of the node, as described above.

Subsequently, the processing proceeds to S102 to calculate an actual n-th node floor reaction force moment $M_{n_act}(n=1,2,3,4,14,23,1423)$. In the robot 1 of the first embodiment, the actual node floor reaction force moment $M_{n_act}(n=1,2,3,4)$ of each leaf node is zero. Further, the actual node floor reaction force moment $M_{n_act}(n=14,23,1423)$ of each node that is not a leaf node is calculated on the basis of the aforesaid expression 16 or expression 17 from $F_{n_act}(n=1,2,3,4)$ obtained in S100 and the desired node floor reaction force central point $Q_n(n=1,2,3,4,14,23,1423)$.

Subsequently, the processing proceeds to S104 wherein the n-th node compensating floor reaction force moment $M_{n_dmd}(n=14,23,1423)$ is determined on the basis of the compensating total floor reaction force moment M_{dmd} determined by the aforesaid posture stabilization control calculator 104. This processing is carried out as described above by the aforesaid compensating total floor reaction force moment distributor 114a.

Subsequently, the processing proceeds to S106 to determine the vectors V_{1423} , V_{14} and V_{23} defined in the

explanation of the hierarchical compliance operation and vectors U_{1423} , U_{14} and U_{23} orthogonal thereto. In the first embodiment, however, the floor reaction force moments in the directions of the vectors U_{1423} , U_{14} and U_{23} cannot be generated; therefore, it is unnecessary to determine U_{1423} , U_{14} and U_{23} .

Supplementally, as in the second embodiment to be described hereinafter, if the number of child nodes of an n -th node is 3 or more, then V_n may be taken in any direction as long as it does not suddenly change timewise; hence, the direction of V_n may be appropriately determined by, for example, setting it to the direction of the X axis of a supporting leg coordinate system or the direction of the body of a robot. Further, U_n is to be orthogonal to V_n .

Subsequently, the processing proceeds to S108 to extract a component Mn_actv in the V_n direction and a component Mn_actu in the U_n direction of an actual n -th node floor reaction force moment $Mn_act(n=14,23,1423)$.

This may be accomplished by carrying out the scalar product calculation of Mn_act and V_n and U_n . Incidentally, if the number of child nodes of an arbitrary n -th node that is not a leaf node is two or less, as in the first embodiment, then the component Mn_actu in the U_n direction is zero. Hence, it is unnecessary to determine Mn_actu .

Subsequently, the processing proceeds to S110 to extract a component Mn_dmdv in the V_n direction and a

component Mn_dmd_u in the Un direction of an n -th node compensating floor reaction force moment $Mn_dmd(n=14,23,1423)$. This may be accomplished by carrying out the scalar product calculation of Mn_dmd and Vn and Un . Incidentally, if the number of child nodes of an arbitrary n -th node that is not a leaf node is two or less, as in the first embodiment, then the component Mn_dmd_u in the Un direction of the n -th node compensating floor reaction force moment Mn_dmd is set to zero.

10 Alternatively, it is unnecessary to determine Mn_dmd_u .

Subsequently, the processing proceeds to S112 to determine a Vn component of an n -th node compensating angle θ_n by multiplying the difference between a value obtained by passing Mn_actv through a filter and a value
15 obtained by passing Mn_dmdv through a filter by a gain Kn (more generally, according to the feedback control law from the difference). In the first embodiment, this processing is carried out as described above on the 14th node, the 23rd node and the 1423rd node by the aforesaid
20 compensating angle determiners 114b, 114c and 114d.

Subsequently, the processing proceeds to S114 to determine a Un component of an n -th node compensating angle θ_n by multiplying the difference between a value obtained by passing Mn_actu through a filter and a value
25 obtained by passing Mn_dmd_u through a filter by the gain Kn (more generally, according to the feedback control law from the difference). However, if the number of child

nodes of an arbitrary n-th node that is not a leaf node is two or less, as in the first embodiment, then an n-th node compensating angle U component is set to zero.

Alternatively, it is unnecessary to carry out the

5 processing of S114.

The above is the subroutine processing of S34 in Fig. 9. Supplementally, the processing of S106 to S114 may be regarded as the processing for determining an n-th node compensating angle such that the actual n-th node floor reaction force moment acting on a desired n-th node floor reaction force central point converges to an n-th node compensating floor reaction force moment (more precisely, the resultant force of the n-th node compensating floor reaction force moment and the desired node floor reaction force moment acting on the desired n-th node floor reaction force central point).

Subsequently, the processing proceeds to S36 of the flowchart of Fig. 9 to calculate the aforesaid deformation compensation amount. This processing is carried out by the aforesaid deformation compensation amount calculator 114n as described above.

Subsequently, the processing proceeds to S38 to correct a desired ground contact portion position/posture on the basis of the compensating angle determined in S34 and to further correct it on the basis of the deformation compensation amount determined in S36, thereby obtaining the corrected desired ground contact portion

position/posture with deformation compensation of each
ground contact portion 10. In the first embodiment, the
corrected desired ground contact portion positions of the
ground contact portions 10 are determined on the basis of
5 the compensating angles θ_{1423} , θ_{14} and θ_{23} as described
above (as explained with reference to the aforesaid 15 and
Fig. 16) by the corrected desired ground contact portion
position/posture calculator 114g. Then, the determined
corrected desired ground contact portion positions are
10 further corrected by the corrected desired ground contact
portion position/posture with deformation compensation
calculator 114h on the basis of the aforesaid deformation
compensation amount $En_cmpn(n=1,2,3,4)$, as described above,
thereby obtaining the corrected desired ground contact
15 portion positions with deformation compensations of the
ground contact portions 10.

The processing from S32 to S38 in Fig. 9 explained
above is the processing of the hierarchical compliance
operation determiner 114.

20 Subsequently, the processing proceeds to S40 to
calculate the joint displacement command of the robot 1
from the desired body position/posture and the corrected
ground contact portion position/posture with deformation
compensation (the corrected ground contact portion
25 position with a deformation compensation in the first
embodiment). This processing is carried out as described
above by the aforesaid robot geometric model 110.

Subsequently, the processing proceeds to S42 to make an actual joint displacement follow the joint displacement command. This follow-up control (servo control) is carried out by the aforesaid displacement controller 112.

5 Subsequently, the processing proceeds to S44 to update time by Δt (the arithmetic processing cycle of the control device 50), and returns to S14 to repeat the processing described above.

10 Owing to the hierarchical compliance operation as in the first embodiment explained above, the controls of node floor reaction forces hardly interfere with each other, thus allowing the node floor reaction forces to be controlled easily and properly also in a mobile robot having three or more ground contact portions. This
15 restrains control interference and also restrains the actual floor reaction force of each node from deviating from a desirable value or from vibrating. Thus, even if a floor surface not only has an undulation or tilt over a large area thereof but also unexpected changes in the
20 floor configuration, including local projections or depressions or slopes, floor reaction forces acting on a legged mobile robot can be properly controlled without being influenced by them much. Moreover, control for stabilizing the posture of a mobile robot can be easily
25 accomplished and the landing shocks to the mobile robot can be reduced, thus allowing the ground contact properties of the mobile robot to be enhanced and also

preventing the mobile robot from slipping or spinning when it travels. Furthermore, the loads of the actuators of the mobile robot can be reduced. Hence, the floor reaction forces of ground contact portions can be properly controlled, so that high posture stability can be obtained.

To supplement the advantages contributing to the stabilization of the posture of a robot, when the entire robot inclines from a state in which the robot is walking as expected on an expected floor surface, the relationship between an inclination angle error θ_{berr} (θ_{berrx} , θ_{berry}) and an increasing amount ΔM of the moment horizontal component about a desired total floor reaction force central point generated in response thereto is preferably a proportional relationship. If not, it is still preferred that expression 24 given below holds for a certain rotational matrix T and a certain diagonal matrix $\text{diag}(a,b)$. Incidentally, T , $\text{diag}(a,b)$ are secondary square matrixes.

$$T \cdot \Delta M = \text{diag}(a,b) \cdot T \cdot \theta_{berr} \quad \dots \text{Expression 24}$$

If these relationships are not satisfied, then the inclination angle error θ_{berr} will not linearly converge when the robot restores its posture from the inclined state, and a precession movement may occur. For instance, in a state wherein the body of a robot inclines forward, the force (restoring force) to fall sideways other than

the restoring force for returning backward excessively acts, and the inclination angle error θ_{berr} does not linearly returns to zero. Instead, a restoring force acts toward back sideways and the inclination angle error θ_{berr} spirally converges to zero.

For the same reason as that described above, in the compliance control, the relationship between a changing rate $d\theta_{berr}/dt$ of the inclination angle error θ_{berr} of the entire robot and an increasing amount ΔM_d of the moment generated in response thereto is also preferably a proportional relationship. If not, it is still preferred that expression 25 given below holds for a certain rotational matrix T and a certain diagonal matrix $\text{diag}(e,f)$. Incidentally, T , $\text{diag}(a,b)$ are secondary square matrixes.

$$T \cdot \Delta M_d = \text{diag}(e,f) \cdot T \cdot d\theta_{berr}/dt \quad \dots \text{Expression 25}$$

In general, if compliance control is independently carried out on each leg of a robot, these relationships may not be satisfied and a precession movement may take place. In the hierarchical compliance control shown in the first embodiment, the relationships of the aforesaid expressions 24 and 25 can be satisfied, so that the convergence of the posture control of the robot is high and it is possible to prevent oscillation or vibration.

In the aforesaid first embodiment, the desired ground contact portion positions have been amended (corrected) so as to rotationally move about node floor reaction force central points without changing the postures of the ground contact portions (without controlling the postures), thereby correcting the relative heights of the ground contact portions from the relative heights of the desired ground contact portion positions. Alternatively, however, only the heights of the ground contact portions may be corrected by moving the desired ground contact portion positions only in the vertical direction. Specifically, a desired ground contact portion position is corrected according to the following procedure.

First, by the following expressions 26 and 27, a vertical position correction amount Z_{14} of a desired 14th node floor reaction force central point and a vertical position correction amount Z_{23} of a desired 23rd node floor reaction force central point are determined.

$Z_{14} = -PQ_{14} * \theta_{1423}$... Expression 26

$Z_{23} = PQ_{23} * \theta_{1423}$... Expression 27

Here, note that the value determined by the aforesaid expression 19 is substituted into θ_{1423} .

Next, the vertical position correction amounts Z_n ($n=1, 2, 3, 4$) of the desired floor reaction force central points of the ground contact portions (the desired node

floor reaction force central points of leaf nodes) are determined according to the following expressions.

$$Z1=-Q14Q1*\theta14+Z14 \quad \dots \text{Expression 28}$$

5 $Z4=Q14Q4*\theta14+Z14 \quad \dots \text{Expression 29}$

$$Z2=-Q23Q2*\theta23+Z23 \quad \dots \text{Expression 30}$$

$$Z3=Q23Q3*\theta23+Z23 \quad \dots \text{Expression 31}$$

10 Here, note that the value determined by the aforesaid expression 23 is substituted into $\theta14$, and the value determined in the same manner as that for $\theta14$ is substituted into $\theta23$.

15 The corrected desired ground contact portion positions are obtained by adding $Z1$, $Z2$, $Z3$ and $Z4$ determined as described above to the desired ground contact portion positions in the vertical direction.

20 Further, in the aforesaid first embodiment, the ground contact portions 10 have been hierarchized as shown in the aforesaid Fig. 6; however, the hierarchical structure does not necessarily have to be decided to be one hierarchical structure beforehand. For example, the hierarchical structure may be changed according to the travel mode (the motion mode of legs when traveling) of the robot 1, including trotting or galloping. For
25 instance, the ground contact portions 10 may be hierarchized as shown in Fig. 23. Fig. 23 illustrates, as in the aforesaid Fig. 3(b), an example wherein the pair of

the first ground contact portion 10 and the second ground contact portion 10 is defined as a 12th node and the pair of the third ground contact portion 10 and the fourth ground contact portion 10 is defined as a 34th node in a period during which all legs #1 to #4 of the robot 1 are all supporting legs. In this example, the desired node floor reaction force central points $Q_n(n=1,2,3,4,12,34,1234)$ of the nodes are set as illustrated. With this arrangement, the aforesaid compliance operation and the estimation of a floor configuration, which will be discussed later, can be performed more accurately in some cases.

[Second Embodiment]

The following will explain a second embodiment of the present invention with reference to the aforesaid Fig. 1 and Fig. 24 to Fig. 34. Referring to Fig. 1, the explanation will be focused on the aspects of a robot 1 of the second embodiment that are different from the robot of the first embodiment. The robot 1 of the second embodiment is provided with, in addition to the first to the fourth legs #1 to #4, a fifth leg #5 and a sixth leg #6 having the same structures as those of the legs #1 to #4. This means that the robot 1 of the second embodiment is a six-legged robot. The fifth leg #5 is behind the third leg #3 and extended from the right side of the body 24 of the robot 1, and the sixth leg #6 is behind the

fourth leg #4 and extended from the left side of the body
24 of the robot 1. The rest of the mechanical structure
of the robot 1 is the same as that of the first embodiment,
so that the like reference numerals as those of the first
5 embodiment will be assigned and the explanation thereof
will be omitted.

The basic concept of the technique of the
hierarchical compliance control of the robot 1 (six-legged
robot) of the second embodiment is the same as that of the
10 first embodiment. However, the hierarchical compliance
control of the second embodiment differs from that of the
first embodiment in that there is a node having three
child nodes and control processing is expanded to handle
them.

15 The following will explain the control processing of
the robot 1 of the second embodiment, focusing mainly on
the different aspects. Regarding the reference numerals
and terms used in the explanation of the second embodiment,
the same reference numerals and terms as those in the
20 first embodiment will be used for those that have the
equivalent meanings as those in the first embodiment, and
detailed explanation thereof will be omitted.

Fig. 24 is a diagram for explaining the hierarchical
structure in the second embodiment, and it is a diagram
25 corresponding to Fig. 3(b) in the first embodiment. As
shown in Fig. 24, in the second embodiment, the six
individual ground contact portions 10 are defined as leaf

nodes (the first to the sixth nodes), and the set of all the six ground contact portions 10 is defined as a root node (the 145236th node). In addition, the set of the first, the fourth, and the fifth ground contact portions 10, which are the ground contact portions of the first leg #1, the fourth leg #4, and the fifth leg #5 is defined as a 145th node, and the set of the second, the third, and the sixth ground contact portions 10, which are the ground contact portions of the second leg #2, the third leg #3, and the sixth leg #6 is defined as a 236th node. In other words, the 145th node is an intermediate node having the first, the fourth, and the fifth nodes (three leaf nodes) as child nodes, and the 236th node is an intermediate node having the second, the third, and the sixth node (three leaf nodes) as child nodes.

In the second embodiment, for example, the set of the three ground contact portions 10 of the 145th node and the set of the three ground contact portions 10 of the 236th node are alternately lifted and landed to move the robot 1. Fig. 24 shows the state wherein both sets are landed (the state wherein both sets are supporting legs). The triangles with the reference marks Q_n ($n=1,2,3,4,5,6$) in the figure correspond to the positions of the ground contact portions 10.

Incidentally, Q_n ($n=1,2,3,4,5,6$) denotes the desired floor reaction force central point of each of the first to the sixth ground contact portions 10, which are leaf nodes

(desired node floor reaction force central points), Q_{145} and Q_{236} denote the desired floor reaction force central points of the 145th node and the 236th node, respectively (desired node floor reaction force central points), and P denotes the desired total floor reaction force central point (= desired ZMP) as the desired floor reaction force central point (desired node floor reaction force central point) Q_{145236} of the root node (the 145236th node). As with the first embodiment, Q_n ($n=1,2,3,4,5,6$) agrees with the central point of each corresponding ground contact portion 10.

The overall functional construction of a control device 50 in the second embodiment is the same as that shown in Fig. 2 explained in conjunction with the aforesaid first embodiment.

In this case, a gait generating device 100 in the second embodiment determines and outputs desired motion trajectories (a desired ground contact portion trajectory and a desired body position/posture trajectory) of the robot 1 and desired floor reaction force trajectories (a desired total floor reaction force central point trajectory and a desired total floor reaction force trajectory), as with that in the first embodiment. In the second embodiment, however, the desired ground contact portion trajectory is the trajectory of the desired ground contact portion position of each of the six ground contact portions 10. If the ground contact portions are provided

such that their postures are controllable, then the trajectory of desired ground contact portion postures is also included in the desired ground contact portion trajectory. Further, the desired total floor reaction force central point trajectories are determined such that they continuously move while existing in a range in which ZMPs may exist at positions not excessively close to the boundaries of the range (e.g., at an approximately central position of the range wherein a ZMP may exist) according to the motion modes of the legs #1 to #6 (especially the positions at which supporting legs are expected to land) in the second embodiment.

A desired floor reaction force distributor 102 in the second embodiment determines desired node floor reaction force central points, the weights of nodes, and desired node floor reaction forces such that the following conditions A') to F') are satisfied, as with the first embodiment.

A') The desired node floor reaction force central point Q_n ($n=1,2,3,4,5,6$) of each leaf node agrees with the central point of the ground contact portion 10 corresponding to the leaf node. More generally, Q_n ($n=1,2,3,4,5,6$) is determined according to a desired gait (a desired motion, such as a desired ground contact portion trajectory). For example, if the desired floor reaction force central point of each ground contact portion 10 is determined by the gait generating device 100,

then the desired node floor reaction force central point Q_n ($n=1,2,3,4,5,6$) may be determined on the basis of the desired floor reaction force determined by the gait generating device 100.

5 B') The desired floor node reaction force central point of the root node agrees with a desired total floor reaction force central point P.

C') The desired node floor reaction force central point Q_n of an arbitrary n-th node ($n=145,236,145236$) having child nodes will be a weighted average point of the desired node floor reaction force central points of the child nodes of the n-th node. More specifically, a desired node floor reaction force central point Q_{145} of a 145th node provides the internally dividing point of a triangle having, as its apexes, desired node floor reaction force central points Q_1 , Q_4 and Q_5 of the first, the fourth and the fifth nodes, which are the child nodes (leaf nodes) thereof (points on a boundary of the triangle being included), and a desired node floor reaction force central point Q_{236} of a 236th node provides the internally dividing point of a triangle having, as its apexes, desired node floor reaction force central points Q_2 , Q_3 and Q_6 of the second, the third and the sixth nodes, which are the child nodes (leaf nodes) thereof (points on a boundary of the triangle being included). Further, a desired node floor reaction force central point Q_{145236} (= desired total floor reaction force central point P) of a 145236th node (root node)

provides an internally dividing point of a segment connecting the desired node floor reaction force central points Q145 and Q236 of the 145th node and the 236th node, which are the child nodes (intermediate nodes) thereof.

5 D') The desired node floor reaction force F_n of an arbitrary n-th node ($n=145, 236, 145236$) having child nodes agrees with the sum (resultant force) of the desired node floor reaction forces of all child nodes of the n-th node, and the desired node floor reaction force F_{145236} of the
10 root node (the 145236th node) agrees with the desired total floor reaction force $F_{totalref}$. Alternatively, the desired node floor reaction force
 F_n ($n=1, 2, 3, 4, 5, 6, 145, 236, 145236$) of each node has the relationship of the aforesaid expression 4a or 4b with the
15 weight of each node.

E') The desired node floor reaction force of a leaf node associated with the ground contact portion 10 not in contact with the ground is zero.

F') The desired node floor reaction force central point, the weight, and the desired node floor reaction force of
20 each node (n-th node ($n=1, 2, 3, 4, 145, 236, 145236$)) continuously change.

G') The weight of a leaf node corresponding to the ground contact portion 10 in a no-contact-with-ground state or
25 the weight of any one of the ancestor nodes of the leaf node is zero.

The weight of the root node has been set to "1" for

the sake of convenience, as with the aforesaid first embodiment.

The processing of a posture error calculator 103 and a posture stabilization control calculator 104 in the second embodiment is the same as that in the first embodiment; a compensating total floor reaction force moment M_{dmd} (M_{dmdx} , M_{dmdy}) is determined as explained in the first embodiment.

An actual floor reaction force detector 108 in the second embodiment, as that in the first embodiment, detects the actual floor reaction forces acting on the ground contact portions 10 (the six ground contact portions in the present embodiment) from the outputs of six-axis force sensors 34 provided on the legs #1 to #6 and converts them into actual floor reaction forces represented by a supporting leg coordinate system (the global coordinate system shown in Fig. 1, which is fixed to a floor).

Primarily on the basis of the final desired trajectories of ground contact portion positions and desired body position/posture, a robot geometric model (inverse kinematics calculator) 110 in the second embodiment calculates joint displacement commands of the robot 1 that satisfy them by inverse kinematics calculation, as that in the first embodiment.

Further, a displacement controller 112 in the second embodiment controls actuators (not shown) of the joints 14

and 15 of the robot 1 so as to make actual joint displacements follow the aforesaid joint displacement commands, as that in the first embodiment.

Further, a hierarchical compliance operation
5 determiner 114 in the second embodiment corrects the desired ground contact portion trajectories of the ground contact portions 10 so as to satisfy the aforesaid requirements 1) and 2) as much as possible, as that in the first embodiment. The present embodiment, however, has
10 intermediate nodes each having three child nodes, so that the specific processing of the hierarchical compliance operation determiner 114 is somewhat more complicated than that in the first embodiment. If a robot is constructed such that the postures of the ground contact portions 10
15 are controllable, then the hierarchical compliance operation determiner 114 should correct the desired ground contact portion trajectories of the ground contact portions 10 to also satisfy the aforesaid requirement 3) as much as possible.

20 Fig. 25 is a block diagram showing the functions of the hierarchical compliance operation determiner 114 of the second embodiment, and it corresponds to Fig. 17 in the first embodiment. Referring to Fig. 25, the hierarchical compliance operation determiner 114 of the
25 second embodiment is equipped with, as its components (functional means), a compensating total floor reaction force moment distributor 114a, compensating angle

determiners 114b, 114c and 114d, a corrected desired ground contact portion position/posture calculator 114g, a deformation compensation amount calculator 114n, and a corrected desired ground contact portion position/posture with deformation compensation calculator 114h, as with the first embodiment. Incidentally, in the second embodiment, compensating angles include a 145236th compensating angle θ_{145236} , a 145th compensating angle θ_{145} , and a 236th compensating angle θ_{236} related to the 145236th node, the 145th node, and the 236th node, respectively, and the compensating angle determiners 114b, 114c and 114d determines θ_{145236} , θ_{145} , and θ_{236} .

The following will explain the processing of the hierarchical compliance operation determiner 114 in the second embodiment, focusing mainly on the aspects different from the first embodiment.

The hierarchical compliance operation determiner 114 in the second embodiment, as that in the first embodiment, determines the translational force component and the moment component of the desired node floor reaction force of each node primarily on the basis of an output of the desired floor reaction force distributor 102, and also determines the translational force component and the moment component of the actual node floor reaction force of each node on the basis of an output of the actual floor reaction force detector 108.

More specifically, referring to Fig. 26, a

translational force component $F_{n_ref}(n=1,2,3,4,5,6)$ of the desired node floor reaction force of each leaf node is identical to the translational force component of the desired node floor reaction force determined by the desired floor reaction force distributor 102, and a translational force component $F_{145236ref}$ of the desired node floor reaction force of the root node is identical to a translational force component $F_{totalref}$ of the desired total floor reaction force determined by the gait generating device 100. Further, a translational force component $F_{n_ref}(n=145,236)$ of a desired node floor reaction force of an intermediate node other than leaf nodes and the root node is determined to be the translational force component of the resultant force of the desired node floor reaction forces of the child nodes of the intermediate node ($F_{145ref}=F_{1ref}+F_{4ref}+F_{5ref}$, $F_{236ref}=F_{2ref}+F_{3ref}+F_{6ref}$). In this case, the parent node of the intermediate node is the root node, so that $F_{145ref}+F_{236ref}=F_{totalref}$. Incidentally, Fig. 26 illustrates the translational force component F_{n_ref} of the desired node floor reaction force of each node in a state wherein all the ground contact portions 10 of the robot 1 in the second embodiment are in contact with the ground.

The moment component of the desired node floor reaction force of node (more precisely, the moment component of the desired node floor reaction force having

the desired node floor reaction force central point of the node as its point of action) is always set to zero.

Referring to Fig. 30, a translational force component $F_{n_act}(n=1,2,3,4,5,6)$ of the actual node floor reaction force of each leaf node is identical to the translational force component of the actual floor reaction force of each ground contact portion 10 detected by the actual floor reaction force detector 108. Further, a translational force component $F_{n_act}(n=145,236,145236)$ of the actual node floor reaction force of each node having child nodes is determined to be the translational force component of the resultant force of the actual node floor reaction forces of the child nodes of the node. Therefore, $F_{145act}=F_{1act}+F_{4act}+F_{5act}$, $F_{236act}=F_{2act}+F_{3act}+F_{6act}$, $F_{145236act} (=F_{totalact}) =F_{145act}+F_{236act}$. Fig. 30 illustrates the translational force component F_{n_act} of the actual node floor reaction force of each node in the state wherein all the ground contact portions 10 of the robot 1 in the second embodiment are in contact with the ground.

Further, referring to Fig. 31, a moment component of the actual node floor reaction force of each leaf node (a moment component having the desired node floor reaction force central point of the leaf node as its point of action) $M_{n_act}(n=1,2,3,4,5,6)$ is basically identical to the moment component of the actual floor reaction force of each ground contact portion 10 detected by the actual

floor reaction force detector 108. In the present embodiment, however, no actual moment occurs at the central point of each ground contact portion 10, i.e., the desired floor reaction force central point of the ground contact portion 10; therefore, the moment component of the actual node floor reaction force of each leaf node is set to zero. Further, regarding the moment component M_{n_act} of the actual node floor reaction force of each n-th node ($n=145, 236, 145236$) that has child nodes, the resultant force of the actual node floor reaction forces of the child nodes of the n-th node is basically determined to be the moment component (this generally does not become zero) acting on the desired node floor reaction force central point of the n-th node.

The compensating total floor reaction force moment distributor 114a in the second embodiment distributes the aforesaid compensating total floor reaction force moment M_{dmd} the aforesaid compensating total floor reaction force moment M_{dmd} (M_{dmdx} , M_{dmdy}) to a 145236th node compensating floor reaction force moment $M_{145236dmd}$, a 145th node compensating floor reaction force moment M_{145dmd} , and a 236th node compensating floor reaction force moment M_{236dmd} .

The 145236th node compensating floor reaction force moment $M_{1423dmd}$ is the desired value of the moment to be generated about a desired total floor reaction force central point P (desired ZMP) by the translational force

component of the floor reaction force of each ground
contact portion 10 generated by manipulating the 145236th
compensating angle θ_{145236} (by rotating the set of the
first, the fourth, and the fifth ground contact portions
5 and the set of the second, the third, and the fifth ground
contact portions about a desired total floor reaction
force central point $P(=Q_{145236})$ by θ_{145236}).

The 145th node compensating floor reaction force
moment M_{145dmd} is the desired value of the moment to be
10 generated about a desired 145th node floor reaction force
central point by the translational force component of the
floor reaction force of each ground contact portion 10
(specifically, the first, the fourth, and the fifth ground
contact portions) generated by manipulating the 145th
15 compensating angle θ_{145} (by rotating the first, the fourth,
and the fifth ground contact portions 10 belonging to the
145th node about a desired 145th node floor reaction force
central point Q_{145} by θ_{145}).

The 236th node compensating floor reaction force
20 moment M_{236dmd} is the desired value of the moment to be
generated about a desired 236th node floor reaction force
central point by the translational force component of the
floor reaction force of each ground contact portion 10
(specifically, the second, the third, and the sixth ground
25 contact portions) generated by manipulating the 236th
compensating angle θ_{236} (by rotating the second, the third,
and the sixth ground contact portions 10 belonging to the

236th node about a desired 236th node floor reaction force central point Q_{236} by θ_{236}).

In the present embodiment, as with the first embodiment, the posture of the robot 1 about the vertical axis is not controlled (because the component of the compensating total floor reaction force moment M_{dmd} about the vertical axis is zero), so that $M_{145236dmd}$, M_{145dmd} , and M_{236dmd} are all moments (horizontal vectors) whose components about the vertical axis are zero, and the compensating angles θ_{145236} , θ_{145} , and θ_{236} are rotational angles about the horizontal axis. In particular, $M_{145236dmd}$ is the moment about the horizontal axis perpendicular to a segment $Q_{145}Q_{236}$.

These node compensating floor reaction force moments $M_{145236dmd}$, M_{145dmd} , and M_{236dmd} are basically determined such that the following conditions 11) and 12) are satisfied.

11) On the 145th node, the 236th node, and the 145236th node, as defined in the aforesaid first embodiment, when corrected desired node floor reaction force central points $Q_{145mdfd}$, $Q_{236mdfd}$, and P_{mdfd} ($=Q_{145236mdfd}$) that satisfy the relational expressions of the following expressions 7a to 9a are introduced, these $Q_{145mdfd}$, $Q_{236mdfd}$, and P_{mdfd} exist in their respective predetermined existence permissible range.

$M145236dmd = (Pmdfd - P) * Ftotalref$... Expression 7a

$M145dmd = (Q145mdfd - Q145) * F145ref$... Expression 8a

$M236dmd = (Q236mdfd - Q236) * F236ref$... Expression 9a

5 The existence permissible ranges of $Q145mdfd$,
 $Q236mdfd$, and $Pmdfd$ are set, for example, as shown in Fig.
29(a) in a state wherein all the ground contact portions
10 of the robot 1 of the second embodiment are in contact
with the ground. More specifically, the existence
permissible range of $Q145mdfd$ is the region on the
triangle in the bold line in the figure (the sides of and
the region in the triangle), and this is the region set in
the triangle having, as its apexes, the desired node floor
reaction force central points $Q1$, $Q4$, and $Q5$ of the child
15 nodes of the 145th node such that it is not excessively
close to the boundary of the triangle $Q1Q4Q5$. The
existence permissible range of $Q236mdfd$ is similar to the
above. Further, the existence permissible range of $Pmdfd$
is the region on the segment in bold line in the figure,
20 and this is the region set on a segment $Q145Q236$
connecting the desired floor reaction force central points
 $Q145$ and $Q236$ of the child nodes of the 145236th node
(root node) such that it is not excessively close to the
end points of the segment $Q145Q236$.
25 12) $Mdmd = M145236dmd + M145dmd + M236dmd$ is substantially
satisfied.

Further, in the present embodiment, the root node (the 145236th node) has two child nodes, so that M145236dmd is limited to a vector in the same direction as that of a horizontal unit vector (this being denoted by V145236) orthogonal to the segment Q145Q236, as with each node compensating floor reaction force moment in the aforesaid first embodiment. Hence, in the present embodiment, M145236dmd, M145dmd, and M236dmd are determined such that they satisfy the following condition 13).

13) The component of $M145236dmd + M145dmd + M236dmd$ in the direction of a vector V145236 takes a value close to the component of Mdmd in the direction of the vector V145236 as much as possible.

M145236dmd, M145dmd, and M236dmd satisfying these conditions 11) to 13) are determined, for example, as follows. First, M145236dmd is determined to be the component of Mdmd in the V145236 direction. However, if the corrected desired node floor reaction force central point Pmdfd determined by the aforesaid 7a does not fall within its existence permissible range, then M145236dmd is corrected such that Pmdfd becomes a point of a boundary of the existence permissible range. Subsequently, Mdmd145 and Mdmd236 are determined such that the vector obtained by subtracting M145236dmd determined as described above

from Mdmd substantially agrees with the sum of Mdmd145 and Mdmd236, and the component of Mdmd145+Mdmd23 in the V145236 direction is close to the V145236 component of Mdmd-Mdmd145236 as much as possible and also satisfies the aforesaid condition 11). In this case, Mdmd145 and Mdmd236 are vectors that are parallel to each other.

Examples of M145236dmd, M145dmd, and M236dmd determined as described above are shown in Fig. 29(b). Supplementally, M145236dmd is the horizontal vector perpendicular to the segment Q145Q236 as described above.

If the posture of the robot 1 about the vertical axis is also controlled, the vertical components of M145236dmd, M145dmd, and M236dmd may be also determined.

Compensating angle determiners 114b to 114d in the second embodiment basically determine node compensating angles θ_{145236} , θ_{145} , and θ_{236} on the basis of the difference between the node compensating floor reaction force moment and the actual node floor reaction force moment (the moment having a desired node floor reaction force central point as the point of action) of each n-th node ($n=145236, 145, 236$) such that the difference is approximated to zero. The examples are shown in Fig. 30 and Fig. 31. In this case, in the present embodiment, θ_{145} is the angle of rotation in the same direction as the difference $M_{145act}-M_{145dmd}$ and about an axis that passes the desired 145th node floor reaction force central point Q145, as shown in Fig. 30, and θ_{236} is the angle of

rotation in the same direction as the difference $M_{236act} - M_{236dmd}$ and about an axis that passes the desired 236th node floor reaction force central point Q_{236} , as shown in Fig. 30. Further, θ_{145236} is the angle of rotation in the same direction as the difference $M_{145236act} - M_{145236dmd}$ (the horizontal direction perpendicular to the segment $Q_{145}Q_{236}$) and about an axis that passes the desired total floor reaction force central point P, as shown in Fig. 31.

However, in the present embodiment also, as with the first embodiment, the node compensating angles θ_{145236} , θ_{145} , and θ_{236} are determined on the basis of the difference between the node compensating floor reaction force moment of an n-th node ($n=145236, 145, 236$) that has been passed through a filter and the actual node floor reaction force moment that has been passed through a filter.

Fig. 32 is a block diagram showing the functions of the compensating angle determiner 114b (θ_{145236} determiner) that determines the node compensating angle θ_{145236} as described above, and Fig. 33 is a block diagram showing the functions of the compensating angle determiner 114c (θ_{145} determiner) that determines the node compensating angle θ_{145} as described above. The processing of the compensating angle determiner 114d (θ_{236} determiner) is the same as the processing of the θ_{145} determiner 114b, so that it will neither be explained nor shown.

The compensating angle determiner (0145236 determiner) 114b first determines the moment $M_{145236act}$ generated about the desired total floor reaction force central point P (the desired 145236th node floor reaction force central point) according to the aforesaid expression 16 or 17 if the translational force component ($F_{1act}+F_{4act}+F_{5act}$) of the resultant force of actual first, fourth, and fifth node floor reaction forces acts on the desired 145th node floor reaction force central point Q145 and the translational force component ($F_{2act}+F_{3act}+F_{6act}$) of the resultant force of actual second, third, and sixth node floor reaction forces acts on the desired 236th node floor reaction force central point Q236. Then, a component $M_{145236actv}$ of the determined $M_{145236act}$ in the direction of a vector V_{145236} is determined by scalar product calculation. Here, the vector V_{145236} is a horizontal unit vector that is perpendicular to the segment Q145Q236. Regarding the 145236th node, it is unnecessary to determine the component of $M_{145236act}$ in a vector U_{145236} direction because the positions of the desired floor reaction force central points of the child nodes (the 145th node and the 236th node) cannot be manipulated about the axis in the direction of a horizontal unit vector U_{145236} perpendicular to V_{145236} .

Subsequently, as with the first embodiment, a difference $M_{145236errv}$ ($=M_{145236actvfilt}-M_{145236dmdvfilt}$) between $M_{145236actvfilt}$ obtained by passing the

M145236actv through a low-pass filter and M145236dmdvfilt obtained by passing a component M145236dmdv of the aforesaid 145236th node compensating floor reaction force moment M145236dmd in the direction of a vector V through a compensation filter is multiplied by a predetermined gain K145236 so as to determine the 145236th node compensating angle θ_{145236} .

The compensating angle determiner (θ_{145} determiner) 114c first calculates a moment M145act generated about the 145th node floor reaction force central point Q145 when translational force components F1act, F4act, and F5act of actual first, fourth, and fifth node floor reaction forces act on desired first, fourth, and fifth node floor reaction force central points Q1, Q4, and Q5, respectively. In this case, M145act to be calculated is formed of components in the directions of vectors V145 and U145, respectively, which are horizontal unit vectors that are orthogonal to each other. The directions of the vectors V145 or U145 may be arbitrary.

Subsequently, a difference M145err (=M145actfilt-M145dmdfilt) between M145actfilt obtained by passing the M145act through a low-pass filter and M145dmdfilt obtained by passing the aforesaid 145th node compensating floor reaction force moment M145dmd (a component in the vector V direction and a component in the vector U direction) through a compensation filter is multiplied by a predetermined gain matrix K145 (diagonal matrix) so as to

determine the 145th node compensating angle θ_{145} . θ_{145} is constructed of an angle component about the axis of the vector V and an angle component about the axis of the vector U.

5 The processing for determining the 236th node compensating angle θ_{236} by the compensating angle determiner (θ_{236} determiner) 114d is carried out in the same manner as the processing of the aforesaid θ_{145} determiner 114c.

10 The processing by the compensating angle determiners 114b to 114d explained above determines a set of the node compensating angles θ_{145236} , θ_{145} , and θ_{236} such that the horizontal component of the actual moment M_{act} acting on the desired total floor reaction force central point P
15 approximates the compensating total floor reaction force moment M_{dmd} .

 As supplementally explained in conjunction with the first embodiment, the node compensating angles θ_{145236} , θ_{145} , and θ_{236} may be determined as follows. For each n-
20 th node ($n=145, 236, 145236$) having child nodes, a floor reaction force central point that causes the horizontal component of the moment of the actual node floor reaction force of the n-th node (the resultant force of the actual node floor reaction forces of all child nodes of the n-th
25 node) to be zero is determined as an actual n-th node floor reaction force central point. Alternatively, a floor reaction force central point that causes the

horizontal component of the moment, which is obtained by subtracting the moment acting on a desired node floor reaction force central point of each node that is generated by the actual node floor reaction force of the node from the moment of the actual node floor reaction force of an n-th node ($n=145, 236, 145236$), to be zero is determined as an actual n-th node floor reaction force central point. Then, the difference between the desired node floor reaction force central point of the n-th node ($n=145, 236, 145236$) and the actual n-th node floor reaction force central point determined as described above, or the difference between the values obtained by passing the node floor reaction force central points through filters, respectively, is defined as a control amount, and the node compensating angles θ_{145236} , θ_{145} , and θ_{236} are determined on the basis of the control amount (e.g., θ_{145236} , θ_{145} , and θ_{236} are determined by multiplying the control amount by a certain gain) so as to approximate the control amount to zero.

A corrected desired ground contact portion position/posture calculator 114g in the second embodiment shown in Fig. 25 corrects the desired ground contact portion position/posture (actually the desired ground contact portion position in the robot shown in Fig. 1) of each ground contact portion 10 so as to obtain a corrected desired ground contact portion position/posture. More specifically, referring to Fig. 30 and Fig. 31, the

desired floor reaction force central points Q_1 , Q_4 , and Q_5 of the first, the fourth, and the fifth nodes, respectively, which are the child nodes of the 145th node, are rotationally moved by the 145th node compensating
5 angle θ_{145} (horizontal vector), the desired floor reaction force central point Q_{145} of the 145th node being the center of rotation. The Q_1 , Q_4 , and Q_5 after the rotational movement are denoted by Q_1' , Q_4' , and Q_5' , respectively. Thus, the 145th node compensating angle
10 θ_{145} is the manipulated variable for moving the relative relationship among the positions of the desired floor reaction force central points Q_1 , Q_4 , and Q_5 of the first, the fourth, and the fifth nodes, which are the child nodes of the 145th node, without moving the position of the
15 desired floor reaction force central point Q_{145} of the 145th node.

Similarly, the desired floor reaction force central points Q_2 , Q_3 , and Q_6 of the second, the third, and the sixth nodes, respectively, which are the child nodes of
20 the 236th node, are rotationally moved by the 236th node compensating angle θ_{236} (horizontal vector), about the desired floor reaction force central point Q_{236} of the 236th node being the center of rotation. The Q_2 , Q_3 , and Q_6 after the rotational movement are denoted by Q_2' , Q_3' ,
25 and Q_6' , respectively. Thus, the 236th node compensating angle θ_{236} is the manipulated variable for moving the relative relationship among the positions of the desired

floor reaction force central points Q2, Q3, and Q6 of the second, the third, and the sixth nodes, which are the child nodes of the 236th node, without moving the position of the desired floor reaction force central point Q236 of the 236th node.

These rotational movements are visually shown in Fig. 30.

Subsequently, the desired floor reaction force central points Q145 and Q236 of the 145th and the 236th nodes, which are the child nodes of the 145236th node, are rotationally moved by the 145236th node compensating angle θ_{145236} about the axial center in the same direction (horizontal direction orthogonal to a segment Q145Q236) as that of the vector (horizontal vector) of the aforesaid error M145236errv, the desired floor reaction force central point P (desired total floor reaction force central point) of the 145236th node being the center of rotation. The Q145 and Q236 after the rotational movement are denoted by Q145' and Q236', respectively, as shown in Fig. 31. Thus, the 145236th node compensating angle θ_{145236} is the manipulated variable for moving the relative relationship between the positions of the desired floor reaction force central points Q145 and Q236 of the 145th and the 236th nodes, which are the child nodes of the 145236th node, without moving the position of the desired floor reaction force central point P of the 145236th node (root node).

Next, referring to Fig. 31, the desired node floor reaction force central points $Q1'$, $Q4'$, and $Q5'$ after the previous rotational movement are moved in parallel by a vector $Q145_Q145'$. This provides final corrected desired node floor reaction force central points $Q1''$, $Q4''$, and $Q5''$ of the first, the fourth, and the fifth nodes. Similarly, the desired node floor reaction force central points $Q2'$, $Q3'$, and $Q6'$ after the previous rotational movement are moved in parallel by a vector $Q236_Q236'$. This provides final corrected desired node floor reaction force central points $Q2''$, $Q3''$, and $Q6''$ of the second, the third, and the sixth nodes.

Lastly, the desired ground contact portion position of an n-th ground contact portion ($n=1,2,3,4,5,6$) is moved in parallel (substantially in the vertical direction) by a vector Qn_Qn'' . This corrects the desired ground contact portion position of each ground contact portion (more precisely, the relative relationship among the desired ground contact portion positions of the ground contact portions 10). More specifically, for each node having child nodes, the manipulated variable (correction amount) of the relative relationship (relative positional relationship) among the desired ground contact portion positions of the ground contact portions 10, which are the descendant nodes of the node, is determined on the basis of the compensating angles $\theta145$, $\theta236$, and $\theta145236$, and combining the manipulated variables (correction amounts)

corrects the mutual relative relationship among the desired ground contact portion positions of the ground contact portions 10.

5 In a robot in which the postures of ground contact portions are controllable and floor reaction force moments can be generated about the desired floor reaction force central points of the ground contact portions, the operation of a foot posture rotation about a desired ground contact portion floor reaction force central point
10 (desired node floor reaction force central point) of each ground contact portion may be performed by the technique shown in Japanese Unexamined Patent Application Publication No. H10-277969 (composite-compliance control). More specifically, as supplementally explained in
15 conjunction with the first embodiment, the desired posture of the n-th ground contact portion may be corrected about Q'' after the n-th ground contact portion is moved in parallel as described above.

A deformation compensation amount calculator 114n in
20 the second embodiment shown in Fig. 25 determines, as with that in the aforesaid first embodiment, a deformation compensation amount $En_cmpn(n=1,2,3,4,5,6)$ for compensating for an influence caused by the deformation of the compliance mechanism 42 of each of the legs #1 to #6.
25 More specifically, the deformation compensation amount calculator 114n determines a deformation amount $En_mdfd(n=1,2,3,4,5,6)$ of the compliance mechanism 42 or

the like of the legs #1 to #6 expected to occur due to a corrected desired ground contact portion floor reaction force $F_{n_refmdfd}(n=1,2,3,4,5,6)$ of each ground contact portion 10 (the desired ground contact portion floor reaction force corrected by adding the node compensating floor reaction force moments $M_{145236dmd}$, M_{145dmd} , and M_{236dmd} to a desired ground contact portion floor reaction force) output from the compensating total floor reaction force moment distributor 114a in the second embodiment by using a mechanism compliance model. This E_{n_mdfd} is multiplied by (-1) to determine the deformation compensation amount E_{n_cmpn} .

The corrected desired ground contact portion position/posture with deformation compensation calculator 114h in the second embodiment shown in Fig. 25 determines, as with that in the first embodiment, the corrected desired ground contact portion position/posture with deformation compensation by adding a corresponding deformation compensation amount E_{n_cmpn} to the corrected desired ground contact portion position/posture (the position/posture determined by the aforesaid corrected desired ground contact portion position/posture calculator 114g) of each ground contact portion 10.

The above is the detailed explanation of the processing of the hierarchical compliance operation determiner 114 in the present embodiment (the second embodiment).

The arithmetic processing of the control device 50 other than that explained above is the same as that of the first embodiment.

Incidentally, the hierarchical structure in the
5 second embodiment may be altered according to an operation mode (traveling mode) or the like of the robot 1, as in the case of the first embodiment. For example, the hierarchical structure may be set as shown in Fig. 34. The example in the figure is equipped with, as
10 intermediate nodes, a 12th node having a first ground contact portion and a second ground contact portion as child nodes (leaf nodes), a 34th node having a third ground contact portion and a fourth ground contact portion as child nodes (leaf nodes), a 56th node having a fifth
15 ground contact portion and a sixth ground contact portion as child nodes (leaf nodes), and a 3456th node having a 56th node and a 34th node as child nodes, the root node having the 3456th node and the 12th node as child nodes. This arrangement makes it possible to perform compliance
20 operations and floor configuration estimations, which will be discussed hereinafter, more accurately in some cases. Incidentally, the meanings of the reference characters in the figure are the same as those shown in the aforesaid Fig. 3(b) or Fig. 24 or the like.

25 [Third Embodiment]

An explanation will now be given of a third

embodiment in which a floor configuration estimating function and a function for correcting the operation of the robot 1 on the basis of the result of the estimation have been added to the robot 1 (six-legged robot) of the second embodiment. In the present embodiment, the explanation will be focused mainly on the six-legged robot shown in the second embodiment; however, supplemental explanation will be added also to a four-legged robot in some cases. In addition, for the convenience of the understanding of the present embodiment, a two-legged robot will be referred to in some cases.

The mechanical construction of the robot 1 in the present embodiment is the same as that shown in Fig. 1 explained in the first or the second embodiment (except that the robot 1 has six legs #1 to #6). Hence, the explanation of the mechanical construction of the robot 1 will be omitted. The functional construction of a control device 50 provided on the robot 1 in the present embodiment is also the same as that shown in the aforesaid Fig. 2. In the present embodiment, however, the hierarchical compliance operation determiner 114 in Fig. 2 has newly added functions, making it different from that in the second embodiment. Further, the processing of the components of the control device 50 except for the hierarchical compliance operation determiner 114 is the same as that of the second embodiment. Thus, the explanation of the present embodiment will be focused

mainly on the processing of the hierarchical compliance operation determiner 114, and a detailed explanation of the processing of the control device 50 other than that will be omitted.

5 Fig. 35 is a block diagram showing the processing functions of the hierarchical compliance operation determiner 114 in the present embodiment. Of the functions, those functions that are different from those in the second embodiment will be explained. A floor
10 configuration estimator 130 as a floor configuration estimating means and an adder 132 that adds an estimated floor configuration error (more specifically, the estimated value of floor height error, which will be discussed later, related to each ground contact portion
15 10) output (estimated) by the floor configuration estimator 130 to corrected desired ground contact portion position/posture have been newly added to the hierarchical compliance operation determiner 114 in the present embodiment, and outputs of the adder 132 in place of
20 corrected desired ground contact portion position/posture are supplied to the corrected desired ground contact portion position/posture with deformation compensation calculator 114h. The rest of the processing of the components of the hierarchical compliance operation
25 determiner 114 is the same as the processing thereof in the second embodiment.

Accordingly, the control processing of the main

routine of the control device 50 in the present embodiment is partly different from the control processing shown in the flowchart of the aforesaid Fig. 9. Fig. 36 is a flowchart showing the control processing of the main routine of the control device 50 in the present embodiment. As illustrated, in the present embodiment, the processing for estimating a floor configuration error (the processing of the floor configuration estimator 130) in S37 is newly added after S36. Furthermore, in S38', desired ground contact portion position/posture are corrected on the basis of the compensating angles θ_{145236} , θ_{145} , and θ_{236} explained in the aforesaid second embodiment and the floor configuration error estimated in S37, and the desired ground contact portion position/posture after the correction is further corrected on the basis of a deformation compensation amount so as to obtain corrected desired ground contact portion position/posture with deformation compensation, which are final desired ground contact portion position/posture. In this case, more specifically, corrected desired ground contact portion position/posture are determined on the basis of the compensating angles θ_{145236} , θ_{145} , and θ_{236} , as in the second embodiment, then the corrected desired ground contact portion position/posture are corrected on the basis of a floor configuration error, and this is further corrected on the basis of a deformation compensation amount, thereby obtaining corrected desired ground contact

portion position/posture with deformation compensation.
The items other than the above are the same as the
processing of Fig. 9.

Hereinafter, the aspects of the present embodiment
5 that are different from the second embodiment will be
specifically explained.

Before starting the detailed explanation of the
present embodiment, the concepts and terms to be used when
the floor configuration estimator 130 performs estimation
10 will be defined as follows. In the explanation here, for
the sake of convenience, schematic diagrams of an average
robot, rather than limiting to the six-legged robot 1 in
the present embodiment, will be used.

As shown in Fig. 37, Fig. 38, and Fig. 39, a floor
15 (or a floor surface) supposed in a desired gait is
referred to as "supposed floor." An actual floor on which
a robot travels is referred to as "actual floor." For the
convenience of explanation, Fig. 37 shows the four-legged
robot explained in the first embodiment, and Fig. 38 and
20 Fig. 39 show a two-legged robot. The meanings of the
terms explained below remain the same in any multi-legged
robots, including the six-legged robot 1 in the present
embodiment.

The desired n-th ground contact portion floor
25 reaction force central point Q_n defined in the
hierarchical compliance control explained in the aforesaid
first and the second embodiments has been the point set at

the central point of an n -th ground contact portion;
however, the floor reaction force central point Q_n may
alternatively be set on the ground contact surface (bottom
surface) of the n -th ground contact portion. In this
5 case, in the desired gait, the point on the supposed floor
surface that is supposed to be in contact with the desired
 n -th ground contact portion floor reaction force central
point Q_n is referred to as "supposed n -th floor contact
point D_n ."

10 As is obvious from the definition, during the period
in which the n -th ground contact portion is in contact
with the ground in the desired gait of a robot, the
desired n -th ground contact portion floor reaction force
central point Q_n and the supposed n -th floor contact point
15 D_n share the same coordinates as observed from a
supporting leg coordinate system (global coordinate
system). In comparison to this, the point at which the
point that corresponds to the desired n -th ground contact
portion floor reaction force central point Q_n on the
20 bottom surface of an actual n -th ground contact portion
when the robot 1 is actually traveling comes in contact
with an actual floor is referred to as "actual n -th floor
contact point D_{nact} ."

Examples showing the relationships among these
25 points are shown in Fig. 37, Fig. 38, and Fig. 39.
Incidentally, Fig. 37 shows a four-legged robot viewed
from the direction of the normal line of a vertical plane

that passes a desired first ground contact portion floor
reaction force central point Q1 and a desired second
ground contact portion floor reaction force central point
Q2 (that is, substantially sideways), Fig. 38 shows a
5 traveling (walking) two-legged robot viewed from the
direction of the normal line of a vertical plane that
passes the desired first ground contact portion floor
reaction force central point Q1 and the desired second
ground contact portion floor reaction force central point
10 Q2 (that is, substantially sideways), and Fig. 39 shows a
two-legged robot substantially in an upright posture
viewed from the direction of the normal line of a vertical
plane that passes the desired first ground contact portion
floor reaction force central point Q1 and the desired
15 second ground contact portion floor reaction force central
point Q2 (that is, substantially from rear).

In these Fig. 37 to Fig. 39, the sections of the
supposed floors on the aforesaid vertical planes are
indicated by thin lines, while the sections of actual
20 floors in the aforesaid vertical planes are indicated by
thick lines. Incidentally, in Fig 37, the desired posture
of the robot (the entire posture of the robot at an
instantaneous value of a desired gait) and the actual
posture are indicated by dashed lines and solid lines,
25 respectively. Further, in Fig. 38 and Fig. 39, the
desired postures of the robots (the entire postures of the
robots at instantaneous values of desired gaits) and

actual ground contact portion position/posture are indicated by thin lines and thick lines, respectively. Actual n-th floor contact points in these situations are the points on actual floor surfaces, and they are at the positions shown in Fig. 37, Fig. 38, and Fig. 39.

The configuration difference of an actual floor surface with respect to a supposed floor surface is referred to as a floor configuration error. As the indexes for quantitatively representing floor configuration errors, an n-th node floor height error and an n-th node floor inclination error are defined as follows.

The height of a floor surface at an n-th floor contact point is referred to as "n-th ground contact portion floor height." In relation to an n-th node that is a leaf, the difference between an actual n-th ground contact portion floor height and a supposed n-th ground contact portion floor height is referred to as "n-th ground contact portion floor height error" or "n-th node floor height error." The inclination of the floor surface at an n-th floor contact point is referred to as "n-th ground contact portion floor inclination." In relation to an n-th node that is a leaf, the difference between an actual n-th ground contact portion floor inclination and a supposed n-th ground contact portion floor inclination is referred to as "n-th ground contact portion floor inclination error" or "n-th node floor inclination error."

An example of the ground contact portion floor inclination error is shown in Fig. 39.

With respect to all j-th nodes, which are leaf nodes, the set of node compensating angles for the relationship between desired j-th ground contact portion position/posture and the height and inclination of a supposed j-th floor surface (specifically, the height and inclination of a supposed floor surface at a supposed j-th floor contact point) and the relationship between corrected desired j-th ground contact portion position/posture that has been corrected by a compliance operation using a set of node compensating angles and the height and inclination of an actual j-th floor surface (specifically, the height and inclination of an actual floor surface at an actual j-th floor contact point) to agree with each other is referred to as "(set of) node floor inclination errors)," and among these, the component of the node floor inclination error corresponding to an n-th node compensating angle is referred to as "n-th node floor inclination error." If an n-th node is a leaf node, then the "n-th node floor inclination error" thus defined agrees with "the n-th node floor inclination error" (= the difference between an actual n-th ground contact portion floor inclination and a supposed n-th ground contact portion floor inclination) defined in relation to leaf nodes previously described.

After all, the set of node floor inclination errors

corresponds to a compensation amount necessary to shift all ground contact portions of a robot that is traveling according to a desired gait from a state in which they are parallel to a desired floor surface to a state in which they are parallel to an actual floor surface.

Therefore, by estimating a floor configuration error while walking and by adding the estimated floor configuration error to desired ground contact portion position/posture, the actual floor reaction force moment of each node will be the same as that when the robot is walking on a supposed floor even if there is a floor configuration error. Naturally, the actual floor reaction force moment of the ground contact portion, which is the actual floor reaction force moment of a leaf node, agrees with a desired ground contact portion floor reaction force moment.

Normally, a floor configuration may be represented using the "n-th node floor inclination error" defined as above. If, however, a certain node has three child nodes, and the desired floor reaction force central points of the three child nodes are aligned on the same straight line or if a certain node has four or more child nodes, then it would be difficult to represent a floor configuration.

Hence, in the following explanation, the following expressions that can be generally applied will be used for n-th nodes that are not leaves. The weights used to determine a predetermined weighted average in the

following definition are to be the same as the aforesaid weights determined as described above by the desired floor reaction force distributor 102.

5 Definition:

When all the heights and inclinations of a desired ground contact portion are set to agree with the corresponding heights and inclinations of an actual floor surface, and when the desired floor reaction force central point of an arbitrary node is expressed by a predetermined weighted
10 average of the desired floor reaction force central points of all child nodes thereof (i.e., an internally dividing point based on a predetermined internal division ratio), on an arbitrary n-th node, the height obtained by
15 subtracting the height (the position in the vertical direction) of the desired floor reaction force central point of a parent node of the n-th node from the height (the position in the vertical direction) of the desired floor reaction force central point of the n-th node is
20 referred to as "actual n-th node relative floor height."

Definition:

When all the heights and inclinations of a desired ground contact portion are set to agree with the corresponding
25 heights and inclinations of a supposed floor surface, and when the desired floor reaction force central point of an arbitrary node is expressed by a predetermined weighted

average of the desired floor reaction force central points of all child nodes thereof (i.e., an internally dividing point based on a predetermined internal division ratio), regarding an arbitrary n-th node, the height obtained by subtracting the height (the position in the vertical direction) of the desired floor reaction force central point of a parent node of the n-th node from the height (the position in the vertical direction) of the desired floor reaction force central point of the n-th node is referred to as "supposed n-th node relative floor height."

The height obtained by subtracting a supposed n-th node relative floor height from an actual n-th node relative floor height is referred to as an "n-th node relative floor height error." The n-th node relative floor height error will take the same value when defined as follows.

Definition:

When all the heights and postures of desired ground contact portions are made to agree with corresponding ground contact portion floor height errors and ground contact portion floor inclination errors, and the desired floor reaction force central point of an arbitrary node is expressed by a predetermined weighted average of the desired floor reaction force central points of all child nodes thereof (i.e., an internally dividing point based on a predetermined internal division ratio), on an arbitrary

n-th node, the height obtained by subtracting the desired floor reaction force central point of a parent node of the n-th node from the desired floor reaction force central point height of the n-th node is referred to as "n-th node relative floor height error."

As is obvious from the definition of the n-th node relative floor height error described above, regarding each node having child nodes, an n-th node relative floor height error of all child nodes thereof represents the relative relationship of floor height errors. Further, regarding each node having child nodes, the weighted average value of all child nodes thereof is zero.

In the present embodiment (the third embodiment), the difference between an actual floor surface and a supposed floor surface on a desired gait (i.e., a floor configuration error) is compensated so as to correct the desired positions/postures of ground contact portions to make the ground contact portions that are to be in contact with the ground properly come in contact with the actual floor surface. Further, in the present embodiment, the n-th node relative floor height error defined as described above is used as a floor configuration parameter representing a floor configuration error, and based on this, each n-th ground contact portion floor height error (floor configuration error) is estimated. Then, based on each estimated n-th ground contact portion floor height error (hereinafter referred to simply as the n-th floor

height error in some cases), the desired position of the n-th ground contact portion 10 is corrected.

Based on the above premises, essential sections of the present embodiment will be explained in detail.

5 The inputs into the floor configuration estimator 130 of the hierarchical compliance operation determiner 114 shown in Fig. 35 are, in general, roughly divided as follows.

1) Desired floor reaction force central points (desired
10 total floor reaction force central points P and desired n-th ground contact portion floor reaction force central points $Q_n(n=1,2,3,4,5,6)$).

2) Supposed floor surface configuration (coordinates of
15 supposed n-th floor contact points and supposed n-th ground contact portion floor inclinations).

3) Final desired postures to be followed by an actual
robot (corrected desired ground contact portion
positions/postures with deformations) or actual joint
displacements or frequency weighted average thereof
20 (weighted average based on a weight having a frequency characteristic).

4) Body posture inclination errors.

5) Actual floor reaction forces (the translational force
component and the moment component of an actual n-th
25 ground contact portion floor reaction force).

Incidentally, in the robot 1 in the present embodiment, the postures of the ground contact portions 10

cannot be controlled, so that the supposed n-th ground contact portion inclination of a supposed floor surface configuration is unnecessary.

Further, in the robot 1 in the present embodiment, the moment component of an actual n-th ground contact portion floor reaction force of an actual floor reaction force is zero. This, therefore, is not required to be supplied to the floor configuration estimator 130.

However, in the explanation of the present embodiment hereinafter, the n-th ground contact portion floor reaction force generally includes the moment component of an actual n-th ground contact portion floor reaction force also, considering a case where the postures of the ground contact portions 10 are controllable. Further, in the following explanation, the total number of ground contact portions will be frequently referred to as "last leaf node number" so as to make it possible to expandably apply the present embodiment easily also to a case where the number of ground contact portions is other than four or six. For example, in the six-legged robot 1 shown in Fig. 1, the last leaf node number is "6".

Fig. 40 is a block diagram showing the processing functions of the floor configuration estimator 130. The functional elements constituting the floor configuration estimator 130 shown in Fig. 40 will be explained. The floor configuration estimator 130 is equipped with a mechanism compliance model 134.

The mechanism compliance model 134 determines the deformation amount of a compliance mechanism 42 or the like of each of the legs #1 to #6 (the compliance mechanism 42 and a link mechanism of each leg) when each of the ground contact portions 10 is subjected to an actual floor reaction force $F_{n_act}(n=1,2,..., \text{last leaf node number})$, and adds the determined deformation amount to the corrected desired ground contact portion position/posture with deformation compensation, which are supplied to the aforesaid robot geometric model 110 (refer to Fig. 2), so as to determine estimated n-th ground contact portion position/posture ($n=1,2, ..., \text{last leaf node number}$), which are the estimated values of the position/posture of an n-th ground contact portion (each ground contact portion) after mechanism deformation (more specifically, the estimated values of the n-th ground contact portion position/posture when it is assumed that an actual body posture agrees with a desired body posture). Incidentally, the corrected desired ground contact portion position/posture with deformation compensation used in this case are the past values of the values or the like determined at the last control cycle.

When determining the estimated ground contact portion position/posture after mechanism deformation, if a follow-up delay of control of a joint displacement of the robot 1 cannot be ignored, then the position/posture obtained by passing corrected desired ground contact

portion position/posture with deformation compensation
through a low-pass filter corresponding to the follow-up
delay may be used instead of using the corrected desired
ground contact portion position/posture with deformation
5 compensation as it is.

Alternatively, from a detected value of an actual
joint displacement of the robot 1, an actual ground
contact portion position/posture without mechanism
deformation, which is an actual ground contact portion
10 position/posture in a case where there is no mechanism
deformation, are determined through a robot geometric
model (the same model as the robot geometric model 110 in
Fig. 2), and the determined values may be used in place of
the corrected desired ground contact portion
15 position/posture with deformation compensation.

Alternatively, a weighted average of the aforesaid
actual ground contact portion position/posture without
mechanism deformation and the corrected desired ground
contact portion position/posture with deformation
20 compensation may be determined by using a frequency weight
(weight having a frequency characteristic), and this may
be used in place of the corrected desired ground contact
portion position/posture with deformation compensation.

Strictly speaking, the actual ground contact portion
25 position/posture without mechanism deformation mentioned
above should be used; however, any one of the above may be
used without much difference as long as the capability of

joint displacement control is high.

Incidentally, the mechanism compliance model 134 is explained in detail in Japanese Unexamined Patent Application Publication No. H10-277969 previously proposed by the present applicant; therefore, no more explanation will be given herein.

Supplementally, in a case where an input to the robot geometric model 110 in Fig. 2 does not include deformation compensation, that is, if corrected desired ground contact portion position/posture without deformation compensation (the position/posture determined by the aforesaid corrected desired ground contact portion position/posture calculator 114g) is supplied to the robot geometric model 110, then the corrected desired ground contact portion position/posture without deformation compensation may be supplied to the mechanism compliance model 134 of the floor configuration estimator 130.

Returning to the explanation of Fig. 40, the estimated ground contact portion position/posture after mechanism deformation ($n=1,2,...,6$) is then rotationally moved by the aforesaid body posture inclination error θ_{berr} , about the desired total floor reaction force central point P being the center of the rotation, thereby to determine n-th estimated ground contact portion position/posture after mechanism deformation ($n=1, 2,..., \text{last leaf node number}$) observed from a global coordinate system (supporting leg coordinate system).

Subsequently, the position of the point corresponding to the desired n-th ground contact portion floor reaction force central point after the mechanism deformation observed from the global coordinate system is determined on the basis of the n-th estimated ground contact portion position/posture after the mechanism deformation (n=1,2,...,last leaf node number) observed from the global coordinate system and the position of the desired n-th ground contact portion floor reaction force central point observed from the desired ground contact portion position of an n-th ground contact portion (the desired position of the representative point of the n-th ground contact portion). Then, the determined position of the point is defined as an instantaneous estimated floor contact point position (instantaneous estimated n-th floor contact point position) $Q_{n_estm'}$. This $Q_{n_estm'}$ corresponds to the estimated value of the instantaneous position of an actual n-th floor contact point. The method for determining the instantaneous estimated floor contact point position $Q_{n_estm'}$ are equivalent to determining Q'' of expression 21 in Japanese Unexamined Patent Application Publication No. H10-277969, so that no further detailed explanation thereof will be given herein.

Subsequently, the result obtained by subtracting the supposed n-th floor contact point position D_n from the instantaneous estimated n-th floor contact point position $Q_{n_estm'}$ provides a bias-included instantaneous n-th

ground contact portion floor height error. This
Zfn_with_bias' corresponds to the instantaneous estimated
value of an n-th ground contact portion floor height error.
In a case where no actual height of a body is detected, as
5 with the present embodiment, a bias error is usually
included. Hence, Zfn_with_bias' is referred to as the
bias-included instantaneous n-th ground contact portion
floor height error.

Here, as previously defined, the supposed n-th floor
10 contact point Dn lies at the same position as a desired n-
th ground contact portion floor reaction force central
point Qn in a period during which an n-th ground contact
portion is in contact with the ground. In a desired gait,
immediately before an n-th ground contact portion comes in
15 contact with the ground, the position of the desired n-th
ground contact portion floor reaction force central point
Qn that is expected at the next ground contact is defined
as the supposed n-th floor contact point Dn. In the
desired gait, immediately after the n-th ground contact
20 portion leaves a floor, the position of the desired n-th
ground contact portion floor reaction force central point
Qn that was expected at the time of leaving the floor is
defined as the supposed n-th floor contact point Dn.

Subsequently, an estimated n-th node floor height
25 error Zfn_estm (n=1,2,...,last leaf node number) is
determined by the floor height error estimation processing
subroutine of the flowchart of Fig. 41 on the basis of the

bias-included instantaneous n-th ground contact portion floor height error $Z_{fn_with_bias}$ ' ($n=1, 2, \dots, \text{last leaf node number}$) and the n-th ground contact portion floor reaction force F_{n_act} ($n=1, 2, \dots, \text{last leaf node number}$).

5 Here, "hierarchical relativization processing" (or "hierarchical relativization") used in the floor height error estimation processing subroutine or the like will be explained.

10 The hierarchical relativization processing is generally defined as the processing for determining the output values of all nodes relative to the sets of input values (the values of predetermined types of state amounts) to all leaf nodes. More specifically, the hierarchization relativity processing is the processing
15 for determining node output values such that the weighted average of output values corresponding to all child nodes of an arbitrary node that is not a leaf node is zero and the input value (state amount) of an arbitrary leaf node agrees with the sum of the output value of the node and
20 the output values of all ancestor nodes of the node.

 Hereinafter, determining the value of a certain type of output BB by the hierarchical relativization processing from a certain type of input (state amount) AA to a leaf node will be referred to as "determining BB by
25 hierarchically relativizing AA."

 The following will explain the algorithm of the hierarchical relativization processing. In general, an

input of the hierarchical relativization processing is an n-th ground contact portion height Z_{fn} (n denoting a leaf node number) and an output thereof is an n-th node relative height Z_{n_rel} ($n=1,2,\dots,\text{last node number}$).

5 Incidentally, the "last node number" means the largest number among all node numbers, and the last node number is, for example, 145236 in the hierarchical structure explained in the second embodiment. Further, in the explanation of the algorithm, the "n-th ground contact
10 portion height" is a designation that generically represents an input of the hierarchical relativization processing, such as the aforesaid n-th ground contact portion floor height or an n-th ground contact portion floor height error, and the "n-th node relative height" is
15 a designation that generically represents an output of the hierarchical relativization processing, such as an n-th ground contact portion relative floor height error, which will be discussed later.

First, a bias-included n-th node height $Z_{n_with_bias}$
20 is determined as follows. If an n-th node is a leaf node (i.e., the ground contact portion), then the value of an n-th ground contact portion height Z_{fn} is substituted into the bias-included n-th node height $Z_{n_with_bias}$. If the n-th node is not a leaf node (i.e., the ground contact
25 portion), then the weighted average of the bias-included n-th node heights $Z_{n_with_bias}$ of all child nodes of the n-th node is determined. The determined weighted average

is defined as the bias-included n-th node height $Z_{n_with_bias}$. It should be noted that a weight $W_j (j=1,2,...)$ determined by the aforesaid desired floor reaction force distributor 102 is used as the weight for each child node.

More specifically, the bias-included n-th node height $Z_{n_with_bias}$ is obtained by expression 32 given below.

10 If the n-th node is a leaf node;

$$Z_{n_with_bias} = Z_{fn}$$

If the n-th node is not a leaf node;

$$Z_{n_with_bias} = \Sigma (Z_{j_with_bias} * W_j)$$

15 where Σ denotes the total sum on j , which is $j \in \{\text{set of child node numbers of the n-th node}\}$

... Expression 32

According to the above rules, the bias-included node height $Z_{n_with_bias}$ ($n=1,2,...,\text{last node number}$) is determined on every node.

20 Lastly, an n-th node relative height Z_{n_rel} is determined by subtracting the bias-included height $Z_{h_with_bias}$ of a parent node of the n-th node (this is supposed to be an h-th node) from the bias-included n-th node height $Z_{n_with_bias}$.

More specifically, the n-th node relative height Z_{n_rel} is determined according to the following expression

33. It should be noted that the h-th node is the parent node of the n-th node.

$Zn_rel = Zn_with_bias - Zh_with_bias$... Expression 33

5

According to the above rule, the node relative floor height Zn_rel (n denoting the number of each node) is determined on every node. It should be noted that a node relative height Zk_rel (k denoting the number of a root node) with respect to a root node is zero. Fig. 42 shows an example of calculation of a node relative height of a four-legged robot shown in the first embodiment, while Fig. 43 shows an example of calculation of a node relative height of the six-legged robot in the present embodiment.

15 The bias-included n-th node height $Zn_rel_with_bias$ may alternatively be determined by the following method, which provides the same results.

If an n-th node is a leaf node (i.e., the ground contact portion), then the value of an n-th ground contact portion height Zfn is substituted into the bias-included n-th node height Zn_with_bias . If the n-th node is not a leaf node (i.e., the ground contact portion), then the weighted average of the bias-included heights of the leaf nodes of all descendants of the n-th node is determined.

25 The determined weighted average is defined as the bias-included n-th node height Zn_with_bias . It should be noted that a weight Wj' is the product of the weight Wj

determined for the node j by the aforesaid desired floor reaction force distributor 102 and the weight determined by the aforesaid desired floor reaction force distributor 102 for an ancestor node of the node j and all nodes, which are the descendant nodes of the n -th node.

More specifically, the bias-included n -th node height $Z_{n_with_bias}$ is obtained by expression 34 given below.

If the n -th node is a leaf node;

$$Z_{n_with_bias} = Z_{fn}$$

If the n -th node is not a leaf node;

$$Z_{n_with_bias} = \Sigma(Z_{j_with_bias} * W_{j'})$$

where Σ denotes the total sum on j , which is $j \in \{\text{set of leaf node numbers of the descendants of a node } n\}$

... Expression 34

Supplementally, the weight $W_{j'}$ in this case agrees with the value obtained by dividing the desired floor reaction force of each leaf node by a desired j -th node floor reaction force if the desired j -th node floor reaction force is not zero.

The above is the hierarchical relativization processing.

The subroutine processing of the estimation processing of a floor height error will now be explained below by mainly using the flowchart of Fig. 41 showing it.

Incidentally, this processing uses an n -th ground contact portion floor height error as an input of the hierarchical relativization processing, and an n -th node relative floor height error as an output. The like symbols as those
5 shown in the aforesaid expressions 32 to 34 or the like will be used as the reference symbols of these input and output.

Referring to Fig. 41, first, in S50, the aforesaid bias-included instantaneous n -th ground contact portion
10 floor height error $Z_{fn_with_bias}'$ is hierarchically relativized to determine an instantaneous n -th node relative floor height error Z_{n_rel}' ($n=1,2,\dots,\text{last node number}$).

Subsequently, in S52, the output obtained by
15 hierarchically relativizing an estimated n -th ground contact portion floor height error, which is an estimated value of the n -th ground contact portion floor height error determined at the last control cycle of the control device 50 (hereinafter referred to as the last estimated
20 n -th ground contact portion floor height error $Z_{fn_estm_p}$), is determined as the last estimated n -th node relative floor height error $Z_{n_rel_estm_p}$ ($n=1,2,\dots,\text{last node number}$). It should be noted that, as the weight of each node used in this hierarchical relativization processing,
25 the weight W_n ($n=1,2,\dots,\text{last node number}$) determined by the aforesaid desired floor reaction force distributor 102 at the current (present) control cycle of the control device

50 is used.

Supplementally, in general, if the weight determined in the current control cycle (hereinafter referred to as the current weight) and the weight determined in the last control cycle (hereinafter referred to as the last weight) are different, then the value of the last estimated relative floor height error of each node determined using the last weight and the value of the last estimated relative floor height error of each node determined using the current weight will be inconveniently different values even if the configuration of an actual floor does not change. Hence, the last estimated node relative floor height error of each node is calculated anew by using the current weight as described above instead of directly using the estimated relative floor height error of each node determined at the last control cycle as the last estimated node relative floor height error of each node.

Subsequently, in S54, an n-th node relative floor height error correction amount candidate value $Zn_inc_cand(n=1,2,\dots,last\text{ node number})$ is determined according to expression 35 given below. The Zn_inc_cand means the provisional value of the correction amount of the error when the n-th node relative floor height error is updated at the current control cycle.

In this case, the n-th node relative floor height error correction amount candidate value Zn_inc_cand is set to the product of the difference between the instantaneous

n-th node relative floor height error Zn_rel' and the last estimated n-th node relative floor height error $Zn_rel_estm_p$ and a predetermined coefficient $(\Delta T / (Testm + \Delta T))$, as shown by expression 35 given below.

5

$$Zn_inc_cand = (Zn_rel' - Zn_rel_estm_p) \\ * \Delta T / (Testm + \Delta T)$$

... Expression 35

where Testm in expression 35 denotes a time constant
10 (the time constant of a primary delay) at the estimation
(update) of an n-th node floor height error, and ΔT is a
control cycle of the control device 50.

Thus, when Zn_inc_cand is set, Zn_inc_cand is added
to $Zn_rel_estm_p$ for each control cycle of the control
15 device 50, causing the value of the result of the addition
to change so as to gradually approximate to Zn_rel' .

Subsequently, in S56, a node request mode (an n-th
request mode mdn_dmd), which is a required value of the
mode of each node, is determined on the basis of a timing
20 of a desired gait.

Specifically, in the aforesaid six-legged robot 1,
an n-th node request mode ($n=1,2,3,4,5,6$), a 145th node
request mode $md145dmd$, a 236th node request mode $md236dmd$,
and a 145236th node request mode $md145236dmd$ are set as
25 shown in the timing chart of Fig. 44 with respect to the
elapse of time of a desired gait, and a current request
mode is determined on the basis thereof. However, if the

gait is different, then the pattern of a node request mode should be changed accordingly. Incidentally, regarding ON/OFF in the timing charts of a first stage (the uppermost stage) and a second stage in Fig. 44, the state in which the ground contact portion is in contact with the ground corresponds to ON, while the state in which it is not in contact with the ground corresponds to OFF.

Supplementally, as the present applicant has disclosed in Japanese Unexamined Patent Application Publication No. H10-277969, in the case of a robot that has feet as ground contact portions and that is capable of estimating floor inclination errors at the ground contact portions, the request mode corresponding to the floor inclination error estimation of the ground contact portions should be set as explained in the Publication.

As shown in Fig. 44, the mode of each node (hereinafter referred to simply as the node mode) comes in ready mode, hold mode, and reset mode.

The ready mode is the mode for estimating a floor configuration. The hold mode is the mode for holding (for maintaining an immediately preceding value) the estimated value of the floor configuration (an estimated n-th ground contact portion floor height error). The hold mode is made to exist in a period during which the estimated value of the floor configuration may diverge and a period during which the accuracy of the estimated value of the floor configuration may deteriorate. Further, the reset mode is

the mode for shifting the estimated value of the floor configuration to a predetermined initial value before the next floor configuration estimation is started (the next ready mode begins).

5 Regarding an n -th node ($n=1,2,3,4,5,6$), which is a leaf node, if an n -th ground contact portion is in contact with the ground on a desired gait (that is, if a desired n -th ground contact portion floor reaction force is not zero), then the n -th node request mode is set to the ready
10 mode. Thereafter, when the n -th ground contact portion leaves a floor on the desired gait (that is, when the desired n -th ground contact portion floor reaction force becomes zero), the n -th node request mode is set to the hold mode immediately thereafter. Then, after a while,
15 the n -th node request mode is set to the reset mode. Further, immediately before the n -th ground contact portion comes in contact with the ground on the desired gait, the n -th node request mode is set to the ready mode.

20 Regarding an n -th node ($n=145,236,145236$), which is not a leaf node, that is, an n -th node having child nodes, if at least one ground contact portion belonging to the n -th node is in contact with the ground on the desired gait, then the n -th node request mode is set to the ready mode. Thereafter, when all ground contact portions belonging to
25 the n -th node leave the floor on the desired gait, then the n -th node request mode is set to hold until immediately thereafter. Alternatively, the n -th node

request mode may be set to the hold mode from immediately before all the ground contact portions belonging to the n-th node leave the floor. Then, after a while, the n-th node request mode is set to the reset mode. Further,
5 immediately before at least one of the ground contact portions belonging to the n-th node comes in contact with the ground on the desired gait, the n-th node request mode is set to the ready mode.

Subsequently, in S58, it is determined whether an
10 estimation enable condition is satisfied, and the mode of each node is finally determined on the basis of the result of the determination and the node request mode. The mode of each node to be determined is one of the aforesaid ready mode, hold mode, and reset node. The aforesaid node
15 request mode has been determined on the basis of whether the ground contact portions are in contact with the ground or not on the desired gait. In S58, the mode of each node is determined, considering whether the ground contact portions are actually in contact with the ground or not.

20 The estimation enable condition is satisfying either expression 36 or 37 given below. In this case, if neither expression 36 or 37 is satisfied, then the estimation enable condition does not hold.

25 $F_{n_act_z} > F_{n_min}$... Expression 36

$Z_{n_rel'} < Z_{n_rel_estm_p}$... Expression 37

where $F_{n_act_z}$ denotes the translational force vertical component of an actual n -th ground contact portion floor reaction force ($n=1,2,\dots,$ last leaf node number).

5

The estimation enable condition is a condition that when an n -th node relative floor height error is estimated (when a floor configuration error is estimated), the estimated value does not diverge. The divergence here means a situation in which, when a correcting operation is performed to modify corrected desired ground contact portion position/posture so as to offset the influence of an actual n -th floor height error by using an estimated n -th floor height error Z_{fn_estm} (the estimated value of the floor configuration error) that has been estimated as it will be discussed later, the estimated n -th floor height error Z_{fn_estm} continues to increase and an n -th ground contact portion moves away from the floor (floats further from the floor).

20 If the estimation of Z_{fn_estm} is ideally executed, a predetermined permissible value F_{n_min} may be zero, whereas in actuality, a detection error of F_{n_act} takes place, causing an estimated value to diverge in some cases. To prevent it, F_{n_min} is set to be a value that is
25 sufficiently larger than a detection error of F_{n_act} .

In the present embodiment, the estimation enable condition is the condition in which divergence described

above does not occur. However, the estimation enable condition may alternatively be a condition in which a predetermined accuracy of estimating a floor configuration can be secured. Hence, in place of the translational
5 force vertical component of the actual n-th ground contact portion floor reaction force F_{n_act} , a component that is perpendicular to a supposed floor surface (or an estimated floor surface (estimated actual floor surface)) out of the translational force components of the actual n-th ground
10 contact portion floor reaction force F_{n_act} may be used.

Incidentally, if a floor configuration error (a configuration error between an actual floor surface and a supposed floor surface) is simply estimated and not reflected in a walking operation, that is, if the
15 correction of the corrected desired ground contact portion position/posture to cancel the influence of a floor configuration error is not carried out by using an estimated value of the floor configuration error, then the estimated value of the floor configuration error does not
20 diverge.

The mode of each node is determined on the basis of the result of the determination on whether the estimation enable condition is satisfied and a node request mode.

25 If an n-th node request mode is the ready mode and the estimation enable condition is satisfied, then the n-th node mode is set to the ready mode.

If an n-th node request mode is the ready mode and the estimation enable condition is not satisfied, then the n-th node mode is set to the hold mode.

If an n-th node request mode is the hold mode, then the n-th node mode is set to the hold mode.

If an n-th node request mode is the reset mode, then the n-th node mode is set to the reset mode.

Thus, an n-th mode is determined to be the ready mode at the end only if the request mode is the ready mode and the estimation enable condition is satisfied.

Subsequently, in S60 to S70, the n-th node relative floor height error ($n=1,2,\dots,\text{last node number}$) associated with each of all nodes is estimated.

Supplementally, as disclosed in Japanese Unexamined Patent Application Publication No. H10-277969, in the case of a robot that has ground contact portions (feet) whose postures can be controlled and that is capable of estimating the floor inclination errors in the ground contact portions, it is preferred to also estimate the floor inclination errors associated with the ground contact portions.

Therefore, the processing of S60 to S70 is configured so as to allow floor configuration errors to be estimated also when the postures of ground contact portions can be controlled.

The following will specifically explain the

processing of S60 to S70. In S62, the quantity of child nodes of an n-th node is determined. At this time, if the number of child nodes (the quantity of child nodes) is two, then in S64, the floor configuration estimation processing for two child nodes, which is the estimation processing of the floor configuration error for the quantity, is carried out. If the number of child nodes is three, then in S66, the floor configuration estimation processing for three child nodes, which is the estimation processing of the floor configuration error for the quantity, is carried out. If the number of child nodes is zero, then it is determined in S68 whether the n-th node ground contact portion permits control of a floor reaction force moment.

The processing for the case where the number of child nodes is zero will be further explained. If the number of child nodes of an n-th node is zero, then the n-th node is a leaf node, and the n-th node corresponds to the ground contact portion. In this case, as described above, first, it is determined in S68 whether the n-th ground contact portion permits control of a floor reaction force moment. Here, for example, in the case of a robot that has feet whose postures can be controlled as ground contact portions and its legs do not include free joints, as with a regular bipedal walking robot, floor reaction force moments can be generated at the ground contact portions. However, in the robot 1 (six-legged robot) in the present embodiment, the ground contact portions 10

engage the spherical joints 12, which are free joints;
therefore, none of the ground contact portions 10 can
generate floor reaction force moments. In this case, no
processing is carried out on the n-th node whose number of
5 child nodes is zero.

Meanwhile, if it is determined in S68 that floor
reaction force moments can be controlled, then ground
contact portion floor inclination error estimation
processing is carried out in S70. This processing is the
10 processing for estimating the floor inclination error in
each ground contact portion. This processing is the
processing in which the foot floor reaction force central
point in the floor inclination estimation processing in
Japanese Unexamined Patent Application Publication No.
15 H10-277969 previously proposed by the present applicant
has been replaced by the desired floor reaction force
central point of an n-th ground contact portion in the
present embodiment. Hence, further detailed explanation
will be omitted in the present description.

20 Next, the aforesaid floor configuration estimation
processing for two child nodes will be explained with
reference to Fig. 45 to Fig. 48. Fig 45 is a flowchart
showing the subroutine processing of the floor
configuration estimation processing for two child nodes,
25 Fig. 46 and Fig. 47 are flowcharts showing the subroutine
processing of S6404 and S6408, respectively, of Fig. 45,
and Fig. 48 is a flowchart showing the subroutine

processing of S6406 and S6410 of Fig. 45.

In the floor configuration estimation processing for two child nodes, the modes of all child nodes of an n-th node having two child nodes (the mode determined in S58 of Fig. 41) are determined in S6400, as shown by the flowchart of Fig. 45. The results of the determination are divided into three, namely, "all ready," "all reset," and "others (else)." In the following explanation, the two child nodes of the n-th node will be denoted as the i-th node and the j-th node.

Here, if it is determined that the mode of the child nodes is "all ready," then it is determined in S6402 whether a resultant force F_{n_z} ($=F_{i_act_z}+F_{j_act_z}$) of the translational force vertical components $F_{i_act_z}$, $F_{j_act_z}$ of the actual node floor reaction forces of the child nodes of the n-th node is larger than a predetermined value F_{n_min2} . In other words, F_{n_z} denotes the translational force vertical component of the resultant force of the actual floor reaction forces of all ground contact portions belonging to the n-th node.

If the determination result of S6402 is YES, then intra-group complete estimation processing for a node having two child nodes (the processing for virtually estimating the node relative floor height error of each of the two child nodes owned by the n-th node) is carried out in S6404. In this processing, estimated node relative floor height errors $Z_{i_rel_estm}$ and $Z_{j_rel_estm}$ of the i-

th node and the j-th node, respectively, which are the two child nodes of the n-th node, are determined (updated) according to the expressions shown in the flowchart of Fig. 46. More specifically, Zi_rel_estm will be

5 representatively explained. A j-th node relative floor height error correction amount candidate value Zi_inc_cand determined in the aforesaid S54 is added to a value $Zi_rel_estm_p$ of Zi_rel_estm in the last control cycle thereby to determine a new estimated j-th node relative
10 floor height error Zi_rel_estm . The same applies to the j-th node.

Further, if the resultant force Fn_z of the floor reaction forces of the two child nodes of the n-th node is smaller than the predetermined value Fn_min2 (if the
15 determination result of S6402 is NO), then it means that the accuracy of estimating a floor configuration error would be excessively deteriorated, so that no substantial estimation processing is carried out, and the intra-group total hold processing for a node having two child nodes
20 (the processing for holding the estimated node relative floor height errors of the two child nodes of the n-th node without updating them) is carried out in S6406. In the hold processing, as shown by the expressions in the flowchart of Fig. 48, the values of the estimated node
25 relative floor height errors Zi_rel_estm and Zi_rel_estm of the i-th node and the j-th node, respectively, are maintained at the values $Zi_rel_estm_p$ and $Zi_rel_estm_p$

at the last control cycle.

Next, if it is determined in S6400 of Fig. 45 that the modes of the two child nodes are "all reset," then intra-group total reset processing for a node having two child nodes (the processing for resetting the estimated node relative floor height error of each of the two child nodes owned by the n-th node) is carried out in S6408. In the reset processing, the estimated node relative floor height errors $Z_{i_rel_estm}$ and $Z_{j_rel_estm}$ of the i-th node and the j-th node, respectively, are updated according to the expressions in the flowchart of Fig. 47 such that they gradually approximate to zero. Incidentally, the meanings of ΔT and T_{estm} in the expressions are the same as those of the aforesaid expression 35.

More generally speaking, the reset processing is the processing in which $Z_{i_rel_estm}$ and $Z_{j_rel_estm}$ are determined to take values that are closer to zero than $Z_{i_rel_estm_p}$ and $Z_{j_rel_estm_p}$ are, while satisfying a condition in which the weighted average value of $Z_{i_rel_estm}$ and $Z_{j_rel_estm}$ is zero, that is,

$$W_i * Z_{i_rel_estm} + W_j * Z_{j_rel_estm} = 0.$$

Incidentally, the reset processing includes a primary delay element, so that infinite time is required for the node relative floor height errors to completely return to zero. Hence, a finite stabilization function generator previously proposed by the present applicant (Japanese Unexamined Patent Application Publication No. H5-324115) may be used

to gradually reset the node relative floor height errors to zero.

Further, if the modes of the two child nodes are "others," that is, if the modes are neither "all ready" nor "all reset" in S6400 of Fig. 45 (for example, if the modes of the two child nodes are all hold modes), then the same processing as that of S6406 (refer to Fig. 48) is carried out in S6410.

As described above, only in a case where the modes of the two child nodes of the n-th node are all ready, and there is no danger in that the divergence takes place in the processing of estimating node relative floor height errors, the substantial estimation processing of the node relative floor height errors of the two child nodes is carried out. And, even if the modes of the child nodes are all ready, if there is a danger of the occurrence of divergence of estimation processing, then the values of the estimated node relative floor height errors of the two child nodes are held. Further, in a situation wherein the actual node floor reaction forces of the two child nodes are both zero, that is, if no actual floor reaction forces act on every ground contact portions 10 belonging to an n-th node, then the node relative floor height errors of the two child nodes are reset so that they are gradually reset to zero.

Referring now to Fig. 49 to Fig. 55, the three-child-node floor configuration estimation processing of

S66 of Fig. 41 will be explained. Fig. 49 is a flowchart showing the subroutine processing of the three-child-node floor configuration estimation processing, Fig. 50 and Fig. 51 are flowcharts showing the subroutine processing of S6604 and S6608 of Fig. 49, Fig. 52 is a flowchart showing the subroutine processing of S6606, S6614, and S6618 of Fig. 49, and Fig. 53 and Fig. 54 are flowcharts showing the subroutine processing of S6612 and S6616, respectively, of Fig. 49.

In the three-child-node floor configuration estimation processing, as shown in the flowchart of Fig. 49, the modes of all child nodes of an n-th node having three child nodes (the modes determined in S58 of Fig. 41) are determined in S6600. The determination results are divided into six, namely, "all ready," "all reset," "only two child nodes are ready," "only one child node is held, and the rest are reset," "only two child nodes are held and the rest is reset," and "others (else)."

Here, in the flowchart of Fig. 49, to explain more generally the floor configuration estimation processing for three child nodes, considerations are given not only to a case where all the ground contact portions 10 belonging to each intermediate node (the 145th node and the 236th node) simultaneously come in contact with the ground or leave a floor, as explained in the aforesaid second embodiment, but also to a case where a desired gait of a robot is generated such that one of the ground

contact portions of each intermediate node is in contact with the ground, while the remaining ground contact portions leave the floor. In this case, unlike the two-child-node type, it is necessary to consider also when the modes of the three child nodes are "only two child nodes are ready," "only one child node is held, and the remaining ones are reset," or "only two child nodes are held, and the remaining are reset." In the following explanation, the three child nodes of an n-th node will be referred to as an i-th node, a j-th node, and a k-th node.

Here, if it is determined that the modes of child nodes are "all ready," then it is determined in S6602 whether a resultant force F_n_z ($=F_{i_act_z}+F_{j_act_z}+F_{k_act_z}$) resultant force of the translational force vertical components $F_{i_act_z}$, $F_{j_act_z}$, and $F_{k_act_z}$ of the actual node floor reaction forces of the child nodes of the n-th node is larger than a predetermined value F_{n_min2} . In other words, F_n_z denotes the translational force vertical component of the resultant force of the actual floor reaction forces of all ground contact portions belonging to the n-th node.

If the determination result of S6602 is YES, then intra-group complete estimation processing for a node having three child nodes (the processing for virtually estimating the node relative floor height error of each of the three child nodes owned by the n-th node) is carried out in S6604. In this processing, estimated node relative

floor height errors $Z_{i_rel_estm}$, $Z_{j_rel_estm}$, and $Z_{k_rel_estm}$ of the i-th node, j-th node, and the k-th node, respectively, which are the three child nodes of the n-th node, are determined (updated) according to the expressions shown in the flowchart of Fig. 50. More specifically, $Z_{i_rel_estm}$ will be representatively explained. An i-th node relative floor height error correction amount candidate value $Z_{i_inc_cand}$ determined in the aforesaid S54 is added to a value $Z_{i_rel_estm_p}$ of $Z_{i_rel_estm}$ in the last control cycle thereby to determine a new estimated i-th node relative floor height error $Z_{i_rel_estm}$. The same applies to the j-th node and the k-th node.

If the determination result of S6602 is NO, then it means that the accuracy of estimating a floor configuration error would be excessively deteriorated, so that no substantial estimation processing is carried out, and the intra-group total hold processing for a node having three child nodes (the processing for holding the estimated node relative floor height errors of the three child nodes of the n-th node without updating them) is carried out in S6606. In the hold processing, as shown by the expressions in the flowchart of Fig. 52, the values of the estimated node relative floor height errors $Z_{i_rel_estm}$, $Z_{j_rel_estm}$, and $Z_{k_rel_estm}$ of the i-th node, the j-th node, and the k-th node, respectively, are maintained at the values $Z_{i_rel_estm_p}$, $Z_{j_rel_estm_p}$, and

Zk_rel_estm at the last control cycle.

Further, if it is determined in S6600 of Fig. 49 that the modes of the three child nodes are "all reset," then intra-group total reset processing for a node having
5 three child nodes (the processing for resetting the estimated node relative floor height error of each of the three child nodes owned by the n-th node) is carried out in S6608. In the reset processing, the estimated node relative floor height errors Zi_rel_estm, Zj_rel_estm, and
10 Zk_rel_estm of the i-th node, the j-th node, and the k-th node, respectively, are updated according to the expressions in the flowchart of Fig. 51 such that they gradually approximate to zero. Incidentally, the meanings of ΔT and Testm in the expressions are the same as those
15 of the aforesaid expression 35.

More generally speaking, the reset processing is the processing in which Zi_rel_estm, Zj_rel_estm, and Zk_rel_estm are determined to take values that are closer to zero than Zi_rel_estm_p, Zj_rel_estm_p, and
20 Zk_rel_estm_p are, while satisfying a condition in which their weighted average value is zero, that is,
$$W_i * Z_{i_rel_estm} + W_j * Z_{j_rel_estm} + W_k * Z_{k_rel_estm} = 0.$$
Incidentally, the aforesaid finite stabilization function generator (Japanese Unexamined Patent Application
25 Publication No. H5-324115) may be used to reset Zi_rel_estm_p, Zj_rel_estm_p, and Zk_rel_estm_p to zero.

Further, if it is determined in S6600 of Fig. 49

that the modes of the three child nodes are "only two child nodes are ready," then it is determined in S6610 whether the translational force vertical component F_{n_z} of the resultant force of the actual node floor reaction forces of the child nodes of an n-th node (the resultant force of the actual floor reaction forces of all ground contact portions 10 belonging to the n-th node) is larger than the predetermined value F_{n_min2} .

If the result of the determination is YES, then the intra-group partial estimation processing for a node having three child nodes (the processing for substantially estimating the node relative floor height error of each of the three child nodes owned by the n-th node) is carried out in S6612. This processing is carried out as shown by the flowchart of Fig. 53. In this case, it is assumed that the i-th node is not in the ready mode, while the j-th node and the k-th node are in the ready mode.

First, in S66120, the mode of the i-th node is determined. if the result of the determination is the hold mode, then a new i-th node relative floor height error correction amount candidate value $Z_{i_inc_cand}'$ is determined to be zero in S66122, or if it is the reset mode, then the new i-th node relative floor height error correction amount candidate value $Z_{i_inc_cand}'$ is determined in S66124 according to the expression in the figure. $Z_{i_inc_cand}'$ determined in S66124 denotes an i-th node relative floor height error correction amount

candidate value for gradually approximating $Zi_rel_estm_p$ to zero. The meanings of ΔT and $Testm$ in the expressions of S66124 are the same as those of the aforesaid expression 35. Supplementally, the aforesaid finite
5 stabilization function generator (Japanese Unexamined Patent Application Publication No. H5-324115) may be used to determine Zi_inc_cand' in S66124.

Subsequently, in S66126, a new j -th node relative floor height error correction amount candidate value
10 Zj_inc_cand' and a new k -th node relative floor height error correction amount candidate value Zk_inc_cand' are determined according to the expressions in the figure.

More specifically, Zj_inc_cand' and Zk_inc_cand' are determined such that they satisfy a condition
15 represented by $Wi*Zi_inc_cand' + Wj*Zj_inc_cand' + Wk*Zk_inc_cand' = 0$ (a condition in which the weighted average value of Zi_inc_cand' , Zj_inc_cand' and Zk_inc_cand' is zero) and a condition represented by $Zj_inc_cand' - Zj_inc_cand = Zk_inc_cand' - Zk_inc_cand$.

20 Subsequently, in S66128, Zi_inc_cand' , Zj_inc_cand , and Zk_inc_cand' determined as described above are added to the values $Zi_rel_estm_p$, $Zj_rel_estm_p$, and $Zk_rel_estm_p$ of the relative floor height errors of the i -th node, the j -th node, and the k -th node at the last
25 control cycle so as to determine new Zi_rel_estm , Zj_rel_estm , and Zk_rel_estm .

By determining Zi_rel_estm , Zj_rel_estm , and

Zk_rel_estm as described above, Zi_rel_estm, Zj_rel_estm, and Zk_rel_estm will be determined such that $Zj_rel_estm - Zk_rel_estm$ approximates to $Zj_inc_cand - Zk_inc_cand$ while satisfying $Wi * Zi_rel_estm + Wj * Zj_rel_estm + Wk * Zk_rel_estm = 0$ at the same time.

If the result of the determination of S6610 of Fig. 49 is NO, then the accuracy of estimating a floor configuration error would be excessively deteriorated, so that no substantial estimation processing is carried out, but the same processing as that of the aforesaid S6606 (refer to Fig. 52) is carried out in S6614.

Further, if it is determined in S6600 of Fig. 49 that the modes of the three child nodes are "only one child node is held and the rest are reset," then the processing for a case where only one child mode is hold and the rest are reset is carried out in S6616. In the processing, new node relative floor height errors Zi_rel_estm, Zj_rel_estm, and Zk_rel_estm are determined according to the expressions shown in the flowchart of Fig. 54. Incidentally, in this case, it is assumed that the mode of the i-th node is the hold mode and the modes of the j-th node and the k-th node are the reset mode. The meanings of ΔT and Testm in the expressions are the same as those in the aforesaid expression 35.

The processing of Fig. 54 is, more generally, the processing for determining Zi_rel_estm to be zero, and determining Zj_rel_estm and Zk_rel_estm to take values

that are closer to zero than $Zj_rel_estm_p$ and $Zk_rel_estm_p$ are, while satisfying $Wi*Zi_rel_estm + Wj*Zj_rel_estm + Wk*Zk_rel_estm = 0$ (a condition in which the weighted average value of Zi_rel_estm , Zj_rel_estm and Zk_rel_estm is zero). Supplementally, by the moment the modes of the j-th node and the k-th node both become the reset mode, their node weights Wj and Wk should have become zero. Hence, based on a condition in that the sum of the weights Wi , Wj and Wk is 1, Wi will be 1 by that moment and $Wi*Zi_rel_estm + Wj*Zj_rel_estm + Wk*Zk_rel_estm = 0$, so that Zi_rel_estm will be zero by that moment. Thus, holding the value of the i-th node Zi_rel_estm means maintaining the value at zero. Therefore, in the processing of Fig. 54, the value of Zi_rel_estm is determined to be zero.

Incidentally, the aforesaid finite stabilization function generator (Japanese Unexamined Patent Application Publication No. H5-324115) may be used in the processing for gradually resetting Zj_rel_estm and Zk_rel_estm to zero.

Further, if it is determined in S6600 of Fig. 49 that the modes of the child nodes are "only two child nodes are held and the rest is reset," then the processing for a case where only two child modes are hold and the rest is reset is carried out in S6618. In the processing, new node relative floor height errors Zi_rel_estm , Zj_rel_estm , and Zk_rel_estm are determined according to

the expressions shown in the flowchart of Fig. 55.

Incidentally, in this case, it is assumed that the modes of the i-th node and the j-th mode are both the hold mode and the mode of the k-th node is the reset mode. The

5 meanings of ΔT and T_{estm} in the expressions are the same as those in the aforesaid expression 35.

The processing of Fig. 55 is, more generally, the processing for holding Zi_rel_estm and Zj_rel_estm at the values at the last control cycle, and determining

10 Zk_rel_estm to take a value that is closer to zero than $Zk_rel_estm_p$ is, while satisfying $Wi*Zi_rel_estm + Wj*Zj_rel_estm + Wk*Zk_rel_estm = 0$ (a condition in which the weighted average value of Zi_rel_estm , Zj_rel_estm and Zk_rel_estm is zero). Supplementally, by the moment the
15 mode of the k-th mode becomes the reset mode, Wk should have become zero.

Incidentally, the aforesaid finite stabilization function generator (Japanese Unexamined Patent Application Publication No. H5-324115) may be used in the processing
20 for gradually resetting Zk_rel_estm to zero.

Further, if it is determined to be "Others" in S6620 of Fig. 49 (e.g., if the modes of the three child nodes are all hold mode), then the same processing as that of the aforesaid S6606 (refer to Fig. 52) is carried out in
25 S6620.

As described above, only in a case where the modes of two or more child nodes are ready out of the modes of

the three child nodes of the n-th node, and there is no danger in that the divergence takes place in the processing of estimating node relative floor height errors, the substantial estimation processing of the node relative floor height errors of the two or more child nodes is carried out. And, even if the nodes of two or more child nodes are all ready, if there is a danger of the occurrence of divergence of estimation processing, then the values of the estimated node relative floor height errors of the three child nodes are held.

As described above, in S60 to S66 of Fig. 41, estimated n-th relative floor height errors $Zn_rel_estm(n=1,2,...,last\ node\ number)$ are determined. Incidentally, the relative floor height error of the root node is zero.

In the processing of the flowchart of Fig. 41, lastly, in S72, the sum of the estimated relative floor height errors of all ancestor nodes of an n-th node ($n=1,2,...,last\ leaf\ node\ number$) and an estimated n-th node relative floor height error is determined, and the determined sum is defined as an estimated n-th ground contact portion floor height error (estimated n-th floor height error) Zfn_estm .

The above is the subroutine processing of the estimation processing of floor height errors in Fig. 40.

Next, returning to the explanation of Fig. 35, the estimated n-th floor height error $Zfn_estm(n=1,2,...,last$

leaf node number) sequentially determined by the floor configuration estimator 130 as described above is added to the corrected desired ground contact portion

position/posture of each ground contact portion 10 by an adder 132 so as to determine corrected desired ground contact portion position/posture with floor configuration error compensation. Then, the corrected desired ground contact portion position/posture with floor configuration error compensation is input, in place of corrected desired ground contact portion position/posture, to the corrected desired ground contact portion position/posture with deformation compensation calculator 114h.

The processing of the control device 50 including the floor configuration estimator 130 and the adder 132 explained above is repeatedly carried out at each control cycle of the control device 50, the estimated n -th floor height error Z_{fn_estm} converges to an actual n -th floor height error. Further, desired ground contact portion positions/postures are corrected on the basis of the estimated n -th floor height errors Z_{fn_estm} corresponding to the ground contact portions so as to absorb an influence exerted by an actual n -th floor height error on an actual floor reaction force.

If all n -th ground contact portions ($n=1,2,\dots,\text{last leaf node number}$) are in contact with the ground, then the point corresponding to a desired n -th ground contact portion floor reaction force central point Q_n on the

actual ground contact surface of an n-th ground contact portion should agree with an actual n-th floor contact point Dn_{act} . Therefore, the aforesaid instantaneous n-th node relative floor height error Zn_{rel}' should not change.

5 In actuality, however, the instantaneous n-th node relative floor height error Zn_{rel}' obtained by the aforesaid calculation algorithm of the aforesaid floor configuration estimator 130 significantly changes due to the vibrations and electrical noises of a mechanical
10 system or control device of the robot 1. Therefore, if the instantaneous n-th node relative floor height error is directly used as an estimated n-th node relative floor height error, and based on this, the estimated n-th floor height error Zfn_{estm} is determined (that is, the sum of
15 the instantaneous relative floor height errors of all ancestor nodes of an n-th node ($n=1,2,\dots,$ last leaf node number) and the instantaneous n-th node relative floor height error is defined as the estimated n-th floor height error Zfn_{estm}), and further, the result obtained by
20 adding the estimated n-th floor height error Zfn_{estm} to the corrected desired ground contact portion position/posture is supplied to the corrected desired ground contact portion position/posture with deformation compensation calculator 114h, as shown in Fig. 35, then
25 the ground contact portions 10 of the robot 1 will oscillate or severely vibrate.

Meanwhile, in the intra-group complete estimation

processing for a node having two child nodes, the intra-group complete estimation processing for a node having three child nodes, and the intra-group partial estimation processing for a node having three child nodes described above, the transfer function from the instantaneous n-th node relative floor height error Z_{n_rel}' to the estimated n-th node relative floor height error $Z_{n_rel_estm}$ will be a primary delay low-pass filter. In other words, the estimated n-th node relative floor height error $Z_{n_rel_estm}$ will be the one obtained by passing the instantaneous n-th node relative floor height error Z_{n_rel}' through a low-pass filter. Therefore, even when the estimated n-th floor height error Z_{fn_estm} determined on the basis of the estimated n-th node relative floor height error $Z_{n_rel_estm}$ is added to the corrected desired ground contact portion position/posture, as shown in Fig. 35, the oscillation or vibration of the ground contact portions 10 will hardly occur. This makes it possible to restrain the ground contact portions 10 from oscillating or vibrating.

Incidentally, in the present embodiment, the time constant of the aforesaid low-pass filter is T_{estm} . Other than by the processing of the floor configuration estimator 130 explained in the present embodiment, it is possible to accomplish a construction in which the transfer function from the instantaneous n-th node relative floor height error Z_{n_rel}' to the estimated n-th

node relative floor height error $Z_{n_rel_estm}$ will be a low-pass filter.

The characteristics of the floor configuration estimator 130 in the present embodiment will now be explained.

Even if each node compensating angle is changed and the corrected desired ground contact portion position/posture with deformation compensation, which are the final desired ground contact portion position/posture, are changed to generate node compensating moments required for the stabilization control of the posture of the robot 1, the point corresponding to the desired n-th ground contact portion floor reaction force central point Q_n of the n-th ground contact portion 10 on an actual ground contact surface remains in agreement with the actual n-th floor contact point D_{nact} as long as the ground contact portions 10 are actually in contact with the ground. Instead, the compliance mechanism 42 or the like of each leg deforms or the position/posture of the body 24 change. In other words, the compliance mechanism 42 or the like or the position/posture of the body 24 change in order to cancel the change of the corrected desired ground contact portion position/posture with deformation compensation.

The floor configuration estimator 130 in the present embodiment cancels the influences exerted on the estimated n-th floor height error Z_{fn_estm} by the deformation amount

of the compliance mechanism 42 or the like, which is calculated by the mechanism compliance model 134 on the basis of an actual floor reaction force, and the body posture inclination error θ_{berr} by the time the estimated n-th floor height error $Z_{fn_estm}(n=1,2,\dots,\text{last leaf node number})$ is calculated from the corrected desired ground contact portion position/posture with deformation compensation. Hence, even if a body posture inclination error occurs or corrected desired ground contact portion position/posture with deformation compensation change, the estimated n-th floor height error Z_{fn_estm} is not influenced thereby.

This means that the processing for estimating a floor configuration is not subjected to interference by the compliance control or posture control of the robot 1. Therefore, even when the estimated n-th floor height error Z_{fn_estm} is added to the corrected desired ground contact portion position/posture, as shown in Fig. 35, the stability allowance (resistance to oscillation) of the control device of the robot 1 hardly reduces. In other words, control and processing will not interfere with each and cause oscillation even if the compliance control, posture control and the floor configuration estimation processing and the operation for correcting a desired gait of the robot 1 by using the estimated value of a floor configuration error are simultaneously performed. This means, in brief, that the leg compensating operation to

cancel the influence exerted on a floor reaction force by
a floor configuration error (the operation for correcting
the position/posture of a ground contact portion) can be
simultaneously performed while simultaneously estimating a
5 plurality of parameters of the floor configuration error.
Moreover, the leg compensating operation for posture
control (the operation for correcting the position/posture
of a ground contact portion) can be simultaneously
performed.

10 Further, if the estimated n-th floor height error
 Z_{fn_estm} of each ground contact portion 10 is added to the
corrected desired ground contact portion position/posture,
as shown in Fig. 35, then even if there is actually an n-
th floor height error, the influence thereof can be offset,
15 so that the actual total floor reaction force will
steadily be the same as that in a case where the robot 1
is traveling on a supposed floor. Furthermore, the
estimation of the estimated n-th floor height error
 Z_{fn_estm} and the correction of corrected desired ground
20 contact portion position/posture by using the estimated n-
th floor height error Z_{fn_estm} are sequentially carried
out for each control cycle; therefore, even if a floor
configuration changes on the way, the n-th floor height
error after the change can be estimated and the influence
25 exerted by the change in the floor configuration can be
cancelled on the basis of the estimated value. However,
the floor configuration estimator 130 includes a low-pass

filter, as mentioned above, so that an actual total floor reaction force is transitionally subject to the influence of a floor configuration error immediately after the ground contact portions 10 come in contact with the ground or if the floor configuration changes on the way.

Thereafter, however, the influence is attenuated by the time constant T_{estm} .

Further, there are the following characteristics.

1) Control is resistant to failure even if a floor configuration error is large. This is because the hierarchical compliance control does not carry out approximation limited to minute compensating angles.

2) The accuracy of estimating floor configuration errors is high.

3) Resistance to the occurrence of oscillation attributable to the interference with the robot posture stabilization control, permitting a shorter time constant for estimation processing to be achieved. This makes it possible to enhance the responsiveness of the leg compensating operation to offset the influence exerted by a floor configuration error on a floor reaction force, so that the transitional influence exerted by the floor configuration error on the floor reaction force can be quickly eliminated.

If there is no correlation in the relationship between the estimated n -th floor height error in a landing period of one step before (a period in which a certain

ground contact portion 10 comes in contact with the ground) and the estimated n-th floor height error in a landing period following the above landing period of one step before when a robot is traveling, then it is preferred to forcibly and gradually converge the estimated n-th floor height error to zero, as shown in the present embodiment. However, if, for example, it is known that the undulation of an actual floor surface not considered in a supposed floor is gentle, then it is considered that there is some correlation in the aforesaid relationship. In this case, the estimated n-th floor height error in the current landing period may be forcibly and gradually converged to the value obtained by multiplying the estimated n-th floor height error in the landing period of one step before by a positive constant that is smaller than 1.

Further, the convergence desired value of an estimated n-th floor height error in the current landing period may be determined by using not only the estimated n-th floor height error in the landing period of one step before but also the estimated n-th floor height error in the landing period of a plurality of steps before. Further, the convergence desired value may be determined by using the estimated n-th node floor height error and the estimated n-th node floor inclination error of another node in the landing period of current step, one step before or a plurality of steps before.

Since the present embodiment (the third embodiment) has been constructed as described above, the estimation of floor configurations, specifically, the floor height errors associated with ground contact portions, can be simultaneously, in other words, compositely, estimated with high accuracy even in a robot having many ground contact portions, which has been difficult to accomplish with conventional technologies. Moreover, if the ground contact portions of a robot are provided such that their postures can be controlled, and floor inclination errors are estimated in addition to floor height errors in the processing for estimating floor configurations, the floor inclination errors can be also simultaneously estimated with high accuracy.

Furthermore, by correcting a desired ground contact portion position/posture trajectory on the basis of the result of estimating a floor configuration, even if a floor configuration is different from a supposed configuration, the influence thereof can be absorbed, making it possible to generate a floor reaction force as desired.

In particular, the steady error of an actual floor reaction force from a control desired value, which has not been completely removed by the hierarchical compliance control that does not include corrections based on the estimated values of floor configuration errors, can be

approximated to zero as much as possible. In other words, the steady errors of floor reaction forces caused by floor configuration errors can be eliminated.

Furthermore, the arrangement has been made such that
5 the estimation of a floor configuration is interrupted in a situation wherein the accuracy of estimating a floor configuration may deteriorate or a situation wherein the estimated value thereof may diverge. This adds to the aforesaid advantages by preventing estimated values from
10 being inappropriate.

Incidentally, the floor configuration estimator 130 of a robot according to the present embodiment is expected to estimate floor configurations by the aforesaid techniques, but it is not essential for the floor
15 configuration estimator 130 to correct motions on the basis of estimated values.

[Fourth Embodiment]

A control device (a floor configuration estimator in
20 particular) of a mobile robot according to a fourth embodiment of the present invention will now be explained. In the fourth embodiment, to explain it in brief, the block diagram of the floor configuration estimator 130 shown in Fig. 40 of the aforesaid third embodiment has
25 been equivalently converted. More specifically, the floor reaction force of each node is estimated on the basis of the estimated value of a floor configuration estimated

immediately before (the past value of an estimated value, such as the estimated value in the last control cycle), a desired gait that has been finally corrected and determined (detailedly, corrected desired ground contact portion position/posture with deformation compensation including a compliance operation) (or an actual joint displacement), and an actual body posture inclination error θ_{berr} . Based on the difference between the estimated value and the actual floor reaction force of each node, the correction amount candidate value of the estimated value of the floor configuration is determined to approximate the difference to zero. If it is determined that the estimation of the floor configuration will not diverge, then the estimated value of the floor configuration that has been estimated immediately before is corrected on the basis of the correction amount candidate value of the estimated value of the floor configuration. This processing corresponds to a hierarchical floor configuration estimating means that is an advanced version of the meaning for estimating a floor inclination related to each foot such that the difference between the supposed moment about the floor reaction force central point of the foot of each leg of a biped mobile robot and an actual moment approximates to zero and the means for estimating the interference angle between both legs such that the difference between the supposed moment about a total floor reaction force central point and an

actual moment approximates to zero in the Japanese
Unexamined Patent Application Publication No. H10-277969
previously proposed by the present applicant.

Thus, the present embodiment differs from the third
embodiment only in the processing of a floor configuration
estimator 130, so that the explanation of the processing
of those other than the floor configuration estimator 130
will be omitted.

Fig. 57 is a block diagram showing the functional
means of the floor configuration estimator 130 in the
present embodiment. Referring to this Fig. 57, the floor
configuration estimator 130 in the present embodiment will
be explained below.

First, based on corrected desired n-th ground
contact portion position/posture with deformation
compensation ($n=1,2,\dots$, last leaf node number) of each
ground contact portion 10, the desired n-th ground contact
portion floor reaction force central point of the ground
contact portion 10 observed from the desired ground
contact portion position of each ground contact portion 10,
and the aforesaid posture inclination error θ_{berr} , the
corrected desired n-th ground contact portion
position/posture with deformation compensation is
rotationally moved by θ_{berr} , about a desired total floor
reaction force central point being the center of the
rotation, so as to determine the corrected desired n-th
ground contact portion position/posture ($n=1,2,\dots$, last

leaf node number) with deformation compensation after rotation. A supposed n-th floor contact position D_n ($n=1,2,\dots,\text{last leaf node number}$) on a desired gait is subtracted from the determined corrected desired n-th ground contact portion position/posture ($n=1,2,\dots,\text{last leaf node number}$) with deformation compensation after rotation so as to determine an n-th ground contact portion interference height Z_{n_int} . This is supplied to a mechanism compliance model (inverse model) provided in a floor configuration estimator 130, thereby determining an estimated n-th ground contact portion floor reaction force, which is the estimated value of the floor reaction force of each ground contact portion 10.

Incidentally, the mechanism compliance model here is used to determine the mutual relative relationship among the estimated ground contact portion floor reaction forces on the basis of the mutual relative relationship among ground contact portion interference heights, and it finds no meaning in absolute values. Further, if the detected value of an actual floor reaction force F_{n_act} of an n-th ground contact portion is smaller than a certain threshold value F_{n_min3} , then it is assumed that the n-th ground contact portion is not in contact with the ground also in the aforesaid mechanism compliance model.

Further, the aforesaid estimated n-th ground contact portion floor reaction force is subtracted from the detected value of the actual floor reaction force F_{nact} of

an n-th ground contact portion ($n=1,2,\dots,\text{last leaf node number}$) to determine the estimated error of the n-th ground contact portion floor reaction force $F_{fn_estm_err}$. The estimated error of the n-th ground contact portion floor reaction force $F_{fn_estm_err}$ is expressed in terms of a force, so that it is converted into a height error by a conversion value C_n (e.g., the reciprocal of a spring constant) and the result is adopted as an n-th ground contact portion floor height error correction amount candidate value $Z_{fn_inc_cand}$. Incidentally, the conversion value C_n is not necessarily a diagonal matrix.

Subsequently, hierarchical relativization is performed by the hierarchical relativization processing described above on the basis of the determined n-th ground contact portion floor height error correction amount candidate value $Z_{fn_inc_cand}$ so as to determine an n-th node relative floor height error correction amount candidate value $Z_n_inc_cand(n=1,2,\dots,\text{last node number})$. Then, based on the n-th node relative floor height error correction amount candidate value $Z_n_inc_cand$, an estimated floor height error (estimated n-th floor height error) $Z_{fn_estm}(n=1,2,\dots,\text{last leaf node number})$ is determined by the subroutine processing of the estimation processing of floor height errors. The subroutine processing of the estimation processing of floor height errors here is identical to the processing of S56 to S72 shown in Fig 41.

It is desirable to carry out the ground contact
portion floor inclination error estimation processing as
explained in conjunction with S70 of Fig. 41 in the case
of a robot that has feet whose postures can be controlled
5 as ground contact portions and is capable of estimating
the floor inclination errors in ground contact portions,
as disclosed in Japanese Unexamined Patent Application
Publication No. H10-277969.

Here, the third embodiment and the fourth embodiment
10 (the present embodiment) will be compared. The fourth
embodiment is, in brief, the converted equivalent of the
block diagram of the floor configuration estimator 130 of
the third embodiment. Hence, the advantages of the fourth
embodiment are the same as the advantages of the third
15 embodiment. Further, as with the third embodiment, it is
not essential to correct motions on the basis of the
estimated values of floor configurations.

In the third and the fourth embodiments, distributed
pressure sensors may be used as floor reaction force
20 sensors. Distributed pressure sensors make it possible to
estimate more finely the deformations of ground contact
portions due to actual floor reaction forces than force
sensors, such as the six-axis force sensor 34, so that the
accuracy in estimating floor configurations can be
25 improved.

Furthermore, as shown in Fig. 1 of Japanese Patent
No. 3035051 by the present applicant, a plurality of

contact sensors may be disposed on a ground contact portion (e.g., on the four corners of the ground contact portion), and it may be determined in which direction the ground contact portion is likely to float on the basis of the output signals thereof. Then, the estimation of a floor configuration in the direction in which a contact sensor that is not in contact with the ground is further likely to float may be interrupted, or the estimation of a floor configuration may be also interrupted when all contact sensors are floating.

[Fifth Embodiment]

In the first to the fourth embodiments described above, the explanations have been given to the cases where the total number of child nodes of a node having child nodes is three or less have been taken as examples; however, also in a case where the number of child nodes is four or more, the concepts of the moments and inclination angles can be expanded as shown below by introducing the concept of a weighted average.

The concept can be expanded for any of desired values, actual values, and errors. Here, therefore, the desired values, the actual values, and errors will not be discriminated; instead, the moment for a general set of ground contact portion floor reaction forces $F_n(n=1,2,...)$ will be expanded and defined as shown below.

A set of the floor reaction forces of an n-th ground contact portion $F_n(n=1,2,\dots,\text{last leaf node number})$ is hierarchically relativized to determine an n-th node relative floor reaction force $F_{n_rel}(n=1,2,\dots,\text{last node number})$.

The number of the child nodes of an n-th node is denoted by r .

The identification number of an j-th child node of the n-th node is denoted by $a_j (j=1,2,\dots,r)$.

The weight of the j-th child node of the n-th node is denoted by $W_j (j=1,2,\dots,r)$.

The column vector having, as a j-th element, the weight of the j-th child node of the n-th node is denoted by U_{Wn} .

Thus, U_{Wn} is defined as shown by the following expression 38, where "T" means transposition, and a column vector can be expressed by transpose a row vector.

$$U_{Wn} = (W_{a1}, W_{a2}, \dots, W_{ar})^T \quad \dots \text{Expression 38}$$

$r-1$ mutually independent vectors orthogonal to the vector U_{Wn} (that is, the scalar product with the vector U_{Wn} is zero) are denoted by $R(1), R(2), \dots, R(r-1)$. $R(j) (j=1,2,\dots,r-1)$ denotes the column vector of r row, 1 column. Incidentally, $R(j) (j=1,2,\dots,r-1)$ are desirably orthogonal to each other, considering the ease of computation and control accuracy. A matrix having $R(j)$

set to a j -th column ($j=1,2,\dots,r-1$) is denoted by H_n . H_n is the matrix of r row, $r-1$ column.

A column vector whose j -th element ($j=1,2,\dots,r$) is a relative floor reaction force F_{aj_rel} of a j -th child node of the n -th node is defined as an n -th group relative floor reaction force vector $F_{n_rel_c}$.

In other words, $F_{n_rel_c}$ is defined by the following expression 39.

$$F_{n_rel_c} = (F_{a1_rel}, F_{a2_rel}, \dots, F_{ar_rel})^T \dots \text{Expression 39}$$

$F_{n_rel_c}$ denotes a column vector of r row, 1 column.

A column vector M_{n_exp} satisfying the following expression 40 is referred to as an n -th node expansion floor reaction force moment.

$$F_{n_rel_c} = H_n * M_{n_exp} \dots \text{Expression 40}$$

M_{n_exp} denotes a column vector of $r-1$ row, 1 column.

For the set of ground contact portion floor reaction forces $F_n(n=1,2,\dots)$, the n -th node expansion floor reaction force moment M_{n_exp} is defined as described above.

More specifically, based on the ground contact portion floor reaction force $F_n(n=1,2,\dots)$, a hierarchized node relative floor reaction force $F_{n_rel}(n=1,2,\dots)$ is determined, and further, a vector having, as its element, the coefficient of the linear combination when a vector

$(Fa1_rel, Fa2_rel, \dots, Far_rel)^T$ having, as its elements, the relative floor reaction forces of all child nodes a_j ($j=a1, a2, \dots, ar$) of an n -th node is expressed by the liner combination of certain predetermined mutually independent
5 vectors $R(j)$ ($j=1, 2, \dots, r-1$) that are orthogonal to a vector $(Wa1, Wa2, \dots, War)^T$ having, as its elements, the weights of all child nodes of the n -th node is referred to as the n -th node expansion floor reaction force moment Mn_exp .

10 Incidentally, a j -th element (the element of a j -th row) of the n -th node expansion floor reaction force moment Mn_exp is referred to as the j -th component of the n -th node expansion floor reaction force moment.

Further, the n -th node expansion floor reaction
15 force moment relative to the set of actual ground contact portion floor reaction forces $F_n(n=1, 2, \dots)$ is referred to as the actual n -th node expansion floor reaction force moment Mn_exp_act .

Further, the n -th node expansion floor reaction
20 force moment relative to the set of desired ground contact portion floor reaction forces $F_n(n=1, 2, \dots)$ is referred to as the desired n -th node expansion floor reaction force moment Mn_exp_ref . The desired n -th node expansion floor reaction force moment is usually set to zero vector.

25 Further, the n -th node expansion floor reaction force moment relative to the set of ground contact portion floor reaction force errors $F_n(n=1, 2, \dots)$ is referred to

as the n-th node expansion floor reaction force moment error Mn_exp_err .

Similarly, the inclination angle relative to a set of general ground contact portion heights $Zn(n=1,2,...)$ is expanded and defined as follows.

A set of ground contact portion heights $Zn(n=1,2,...,last\ leaf\ node\ number)$ is hierarchically relativized to determine an n-th node relative height $Zn_rel(n=1,2,...,last\ node\ number)$.

A column vector whose j-th element ($j=1,2,...,r$) is a relative height Zaj_rel of a j-th child node of the n-th node is defined as an n-th node relative height vector Zn_rel_c .

In other words, Zn_rel_c is defined by the following expression 41.

$$Zn_rel_c = (Za1_rel, Za2_rel, ..., Zar_rel)^T \dots \text{Expression 41}$$

A column vector θn_exp satisfying the following expression 42 is referred to as an n-th node expansion floor reaction force inclination angle.

$$Zn_rel_c = Hn * \theta n_exp \dots \text{Expression 42}$$

θn_exp denotes a column vector of r-1 row, 1 column.

More specifically, based on the ground contact

portion height $Z_n(n=1,2,\dots)$, a hierarchized node relative height $Z_{n_rel}(n=1,2,\dots)$ is determined, and further, a vector having, as its element, the coefficient of the linear combination when a vector

5 $(Za1_rel, Za2_rel, \dots, Zar_rel)^T$ having, as its elements, the relative heights of all child nodes a_j ($j=1,2,\dots,r$) of an n -th node is expressed by the liner combination of certain predetermined mutually independent vectors $R(j)$ ($j=1,2,\dots,r-1$) that are orthogonal to a vector
10 $(Wa1, Wa2, \dots, War)^T$ having, as its elements, the weights of all child nodes of the n -th node is referred to as the n -th node expansion inclination angle θ_n .

By using the expansion floor reaction force moment and the expansion inclination angle defined as described
15 above, the compliance control and the processing for estimating floor configurations are expanded almost as they are for a case where the number of the child nodes of an a -th node is four or more. The following will explain an example thereof as a fifth embodiment. In the fifth
20 embodiment, the functional construction of a control device of a robot is the same as that shown in the aforesaid Fig. 2. In this case, the functional construction of a hierarchical compliance operation determiner may be the same as that explained with
25 reference to the aforesaid Fig. 35 except for a compensating total floor reaction force moment distributor, a compensating angle determiner, and a floor configuration

estimator.

[Expanding the processing of the compensating total floor reaction force moment distributor]

5 For example, the processing of the compensating total floor reaction force moment distributor in the hierarchical compliance operation determiner is expanded as shown below.

10 The expansion floor reaction force moment to be generated in addition to a desired n-th node expansion floor reaction force moment Mn_exp_rel (normally zero) to restore the posture of a robot is referred to as an n-th node compensating expansion floor reaction force moment Mn_exp_dmd .

15 Expression 43 given below holds between the n-th node compensating expansion floor reaction force moment Mn_exp_dmd and the n-th node compensating floor reaction force moment Mn_dmd . However, Cn_mech denotes a predetermined coefficient matrix (the matrix of 2 rows, r-
20 1 column) determined by a desired node floor reaction force central point and the compliance characteristic of the mechanism of the robot.

$$Mn_dmd = Cn_mech * Mn_exp_dmd \quad \dots \text{Expression 43}$$

25

Meanwhile, generalizing the aforesaid expression 10 provides the following expression 44.

$$M_{dmd} = \Sigma M_{n_dmd} \quad \dots \text{Expression 44}$$

where Σ means the total sum on all n-th nodes.

5 Hence, the compensating total floor reaction force
moment distributor may determine the n-th node
compensating expansion floor reaction force moment
 $M_{n_exp_dmd}$ ($n=1,2,\dots$) and the n-th node compensating
floor reaction force moment M_{n_dmd} such that expression 43
10 and expression 44 are satisfied.

[Expanding the processing of the compensating angle
determiner (θ_n determiner)]

15 The processing of the n-th node compensating angle
determiner in the fifth embodiment is carried out as
follows. For example, in the processing of the θ_{145}
determiner in the third embodiment (refer to Fig. 25 and
Fig. 33), the processing until M_{145act} is determined is
replaced by the processing for determining the aforesaid
20 actual n-th node expansion floor reaction force moment
 $M_{n_exp_act}$ on the basis of the actual floor reaction force
of each ground contact portion, 145 is replaced by n, and
the dimension of the compensation filter, the low-pass
filter, and gain K_n in Fig. 33 may be expanded to the
25 number obtained by subtracting 1 from the number of child
nodes of an n-th node. The compensating angle θ_n of the
n-th node can be determined by the processing that has

been replaced as described above.

[Estimating a floor configuration by using an expansion
floor reaction force moment]

5 As described below, the processing of the floor
configuration estimator may partly incorporate a technique
using the concept of the expansion floor reaction force
moment.

10 In place of the processing shown in Fig. 56 of the
floor configuration estimator explained in the aforesaid
fourth embodiment, the processing shown in the block
diagram of Fig. 57 is used to estimate floor configuration
errors.

15 Referring to Fig. 57, this processing will be
explained. First, an n-th node expansion floor reaction
force moment estimation error $Mn_exp_estm_err$
corresponding to an n-th ground contact portion floor
reaction force estimation error Ffn_estm_err ($n=1,2,\dots$)
is determined according to the definition of the expansion
20 moment from the difference between the estimated n-th
ground contact portion floor reaction force calculated as
explained in conjunction with the aforesaid Fig. 56 and
the actual floor reaction force of the n-th ground contact
portion (the set of differences for each node).

25 Incidentally, the aforesaid vector $R(j)$ required to
determine the n-th node expansion floor reaction force
moment estimation error is determined on the basis of the

weight of each node.

Subsequently, as shown in expression 45 given below, the n-th node expansion floor reaction force moment estimation error $Mn_exp_estm_err$ is multiplied by a predetermined coefficient matrix Kn_cmpl thereby to determine an n-th node expansion inclination angle correction amount candidate value θn_inc_cand , which is the candidate value of the correction amount of the n-th node expansion inclination angle.

$$\theta n_inc_cand = Kn_cmpl * Mn_exp_estm_err \quad \dots \text{Expression 45}$$

Incidentally, Kn_cmpl is not necessarily a diagonal matrix.

Subsequently, a coefficient for a vector $R(j)$ ($j=1,2,\dots,r-1$) is defined as the j-th element of θn_inc_cand to determine a vector obtained by linearly combining the vectors $R(j)$. The determined vector is defined as the n-th node relative floor height error correction amount candidate value Zn_inc_cand , which is the candidate value of the correction amount of the n-th node relative floor height error.

In other words, Zn_inc_cand is determined according to the following expression 46.

$$Zn_inc_cand = Hn * \theta n_inc_cand \quad \dots \text{Expression 46}$$

As described above, the processing for determining the n-th node floor reaction force estimation error $F_{n_estm_err}$ to the n-th node relative floor height error correction amount candidate value $Z_{n_inc_cand}$ may be replaced from the one shown in Fig. 56 to the one shown in Fig. 57.

The arithmetic processing of Fig. 57 other than the above is the same as the arithmetic processing of Fig. 56.

The subroutine processing of the floor height error estimation processing in the fifth embodiment requires the processing for a case where the number of child nodes of an n-th node is four or more. This processing expands the aforesaid floor configuration estimation processing for three child nodes (refer to Fig. 41), and if the ground contact portion corresponding to a child node j is likely to float and diverge, then the estimated j-th node relative floor height error $Z_{j_rel_estm}$ is maintained at the last value $Z_{j_rel_estm_p}$ (the j-th node relative floor height error correction amount candidate value $Z_{j_inc_cand}$ is set to zero), as with the floor configuration estimation processing for three child nodes. Further, the estimated node relative floor height errors $Z_{k_rel_estm}$ of the remaining child nodes are determined such that they approximate to the value obtained by adding a certain predetermined bias value c to the sum of the last estimated k-th node relative floor height error

Zk_rel_estm_p and Zn_inc_cand. However, the bias value c is determined such that the weighted average of the estimated node relative floor height errors of all child nodes of the n-th node is zero.

5 As described above, the floor configuration estimation processing can be expanded also when there is a node having four or more child nodes. However, the arithmetic processing will be easier if a hierarchical structure is determined not to include four or more child
10 nodes rather than carrying out such processing.

[Sixth Embodiment]

Referring now to Fig. 58 to Fig. 65, a control device for a mobile robot according to a sixth embodiment
15 of the present invention will be explained. Fig. 58 and Fig. 59 are side views showing a legged mobile robot 51 according to the sixth embodiment (a bipedal mobile robot in the present embodiment), the portion of a knee joint 56, which will be discussed later, being in contact with a
20 floor (kneeling). Incidentally, Fig. 58 schematically shows the robot 51 as a linear link assembly.

An object of the invention related to the present embodiment is to stably control the posture of a robot by manipulating a reaction force (external force) received
25 from a floor, including an object fixed on the floor, in a state wherein a portion, such as a knee, an elbow, or a torso other than the distal portions of the legs or arms

of the robot is in contact with the floor or the object fixed (set) on the floor (an object regarded as a material extended from the floor).

5 More specifically, the object is to permit posture control in a state wherein the robot is on its knees or in a state wherein it is sitting on a chair.

10 A conventional publicly known human-like robot is not provided with sensors for detecting floor reaction forces on, for example, its knees, so that it has been impossible to control the floor reaction forces acting on the knees. For instance, in the conventional human-like robot, when the robot is on its knees as shown in Fig. 58 and Fig. 59, the floor reaction forces acting on the right and left knees are dependent on (governed by) the
15 concavities and convexities of a floor, and the joint angles of legs have not been adjusted on the basis of the concavities and convexities of the floor. Hence, there have been some cases where the portions of the robot in contact with the floor shake due to concavities and
20 convexities of the floor, leading to unstable ground contact states of the ground contact portions. And, in such a state, an attempt to make the robot move or work sometimes has caused instability of the posture of the robot.

25 Further, when, for example, the robot stands up from the state wherein it is kneeling, there has been a danger of the robot falling down if an actual floor inclination

is different from the inclination supposed in a desired gait, because the position of the center-of-gravity of the robot is not properly controlled and the robot tries to stand up with its body posture inclined.

5 Further, in a case where the robot sitting on a chair operates or works while maintaining its posture stable, it is preferred that not only the floor reaction forces acting on the feet of the legs of the robot but also the reaction forces acting from the chair onto the
10 buttocks of the robot can be properly controlled so as to restore the posture of the robot to a proper posture when it stands up from the chair or sits onto the chair.

 Conceptually, if an object, such as a chair, which is fixedly set on a floor is considered as a part of a
15 floor, then the aforesaid reaction forces may be said to be floor reaction forces in a broad sense.

 With the view of the problems with the conventional device as described above, the sixth embodiment solves the aforesaid problems, and in a state wherein portions of a
20 mobile robot, such as the knees, elbows, the torso, and buttocks, other than the distal portions of legs or arms are in contact with a floor or an object considered as a material extended from the floor and subjected to reaction forces, it properly controls not only the reaction forces
25 acting on the distal portions of the legs or arms of a robot but also the reaction forces acting on the portions other than the distal portions of the legs or arms, while

using the control of the hierarchical compliance described above, thereby making it possible to keep the posture of the mobile robot stable.

The following will explain the sixth embodiment in more detail by taking the robot (bipedal mobile robot) 51 shown in Fig. 58 and Fig. 59 as an example.

First, the mechanical construction of the robot 51 will be explained. In the robot 51, two legs (link mechanisms) 52 (one leg being not shown) are extended from the bottom end of a body (base) 53. Further, two arms (link mechanisms) 54 (one arm being not shown) are extended from upper part of the body 53. Each leg 52 is provided with a hip joint 55, a knee joint 56, and an ankle joint 57 at its proximal portion adjacent to the body 53 (the portion connected to the body 53), its middle portion, and its distal portion, respectively, which are operated by actuators, such as electric motors, and a foot 58 is connected to the distal portion of each leg 52 through the ankle joint 57. Similarly, each arm 54 is provided with a shoulder joint 59, an elbow joint 60, and a wrist joint 61 at its proximal portion adjacent to the body 53 (the portion connected to the body 53), its middle portion, and its distal portion, respectively, which are operated by actuators, such as electric motors, and a hand 62 is connected to the distal portion of each arm 54 through the wrist joint 61. In this example, the joints 55, 56, and 57 of each leg 2 are joints having, for

example, 3 degrees of freedom, 1 degree of freedom, and 2 degrees of freedom, respectively, and the foot 58 has 6 degrees of freedom relative to the body 53. Further, the shoulder joint 59, the elbow joint 60, and the wrist joint 61 of each arm 54 are constructed such that their degrees of freedom allow the hand 62 to have a degree of freedom of 6 degrees or more with respect to the body 53.

Although not shown, the body 53 of the robot 51 is provided with a control device 50 similar to that of the aforesaid first embodiment. Further, a head 63 is provided at the upper end of the body 53.

In this robot 1, in the state wherein the robot 1 is on its knees (particular posture state), as shown in Fig. 58 and Fig. 59, the portions of the foot 58 of each leg 52 and each knee joint 56 (more specifically, the surface portion of a link (shank link) connecting the knee joint 56 and the ankle joint 57 at near the knee joint 56. Hereinafter referred to simply as the knee) and the hand 62 of each arm 54 are ground contact portions. And, in the present embodiment, as shown in Fig. 59, the knee, which is a ground contact portion, is provided with a floor reaction force sensor 90 (load sensor). The floor reaction force sensor 90 is constructed of a main body (sensor part) 92 and a soft member (elastic member) 94, such as a sponge. The main body 92 is fixed to the knee (leg link), and the outside of the main body 92 is covered with a soft member (elastic member) 94. To enhance the

accuracy of the compliance control in the knee, it is desirable to shape the surface (ground contact surface) of the soft member 94 into a round convex surface in addition to covering the knee with the soft member 94. This

5 arrangement reduces the nonlinearity of the relationship between a corrective operation of a desired motion of the robot 51 and a floor reaction force, resulting in better control performance of the compliance control.

Incidentally, although not shown, the foot 58 and the

10 ankle joint 57 are connected through a floor reaction force sensor, such as a six-axis force sensor, and the compliance mechanism. Similarly, the hand 62 and the

wrist joint 61 are connected through a floor reaction force sensor, such as a six-axis force sensor, and the

15 compliance mechanism, which are not shown. The connecting constructions may be ones that are publicly known.

The floor reaction force sensor 90 of the ground contact portion of the knee joint may be any one of the following.

20 1) Sensor that detects only the translational force in the direction perpendicular to the surface of a ground contact portion that comes in contact with a floor (ground contact surface).

25 2) Sensor that detects not only the translational force in the direction perpendicular to the surface of a ground contact portion that comes in contact with a floor (ground contact surface) but also the translational force in a

direction other than the direction perpendicular to the contact surface.

3) Distributed pressure sensor

4) Sensor that detects moments in addition to

5 translational forces (e.g., six-axis force sensor)

Alternatively, a displacement sensor for detecting the deformation (distortion) of the aforesaid soft member 94 may be used in place of one that directly detects a load.

In the present embodiment, as the floor reaction force sensor 90, the sensor of the above 2) will be used. To further enhance the accuracy of the compliance control, the sensor of the above 3) or 4) may be used as the floor reaction force sensor 90. Incidentally, as the structure of the knee, a floor reaction force sensor may be added to a protective pad provided with a spring (a pad for protecting the knee), as disclosed in Japanese Unexamined Patent Application Publication No. 2000-62760 previously proposed by the present applicant.

In the present embodiment, the hierarchical structure as shown in Fig. 61 is set for the robot 51 on its knees as described above. Specifically, the right foot 58, the left foot 58, the right knee, the left knee, the right hand 62, and the left hand 62 as the ground contact portions are associated with a first node, a second node, a third node, a fourth node, a fifth node,

and a sixth node, respectively, which are leaf nodes.

Further, a 12th node having the first node and the second node as child nodes, a 34th node having the third node and the fourth node as child nodes, a 56th node having the

5 fifth node and the sixth node as child nodes, and a 1234th node having the 12th node and the 34th node as child nodes have been set as intermediate nodes. Further, a 123456th

node having the 1234th node and the 56th node as child nodes has been set as the root node. Further, according

10 to the policy similar to that in the aforesaid first embodiment and the like, a desired floor reaction force central point Q_n ($n=1,2,3,4,5,6,12,34,56,1234,123456$) is associated with each node, as shown in the figure.

Incidentally, the desired floor reaction force central

15 point Q_{123456} of the 123456th node, which is the root node, is identical to a desired total floor reaction force central point P .

In the present embodiment, the control device 50 is supposed to have a functional construction similar to that shown in the aforesaid Fig. 2.

In this case, the desired ground contact portion trajectory of a desired motion in a desired gait output by a gait generating device 100 in the present embodiment is constructed of the desired position/posture trajectory of each hand 62, the desired position/posture trajectory of each foot 58, and the desired position trajectory of each knee. In this case, the gait generating device 100

preferentially determines desired foot positions/postures (desired first and second ground contact portion positions/postures), desired hand positions/postures (desired fifth and sixth ground contact portion positions/postures), and desired knee positions (desired third and fourth ground contact portion positions) so that the feet 58, the hands 62, and the knees come in contact with the ground on a supposed floor surface as required for the gait, then determines a desired ZMP (desired total floor reaction force central point) in a supporting polygon, which is a minimum convex polygon that includes the desired ground contact point (or a desired ground contact line or a desired ground contact surface) of each ground contact portion, and then desired body position/posture are determined by using a dynamic model of the robot 1 such that the desired foot positions/postures, the desired hand positions/postures, the desired knee positions, and the desired ZMP are satisfied.

If the head 63 can be moved with respect to the body 53, then the desired position/posture trajectory of the head 63 is included in a desired motion.

In the present embodiment, the arithmetic processing of the robot geometric model (inverse kinematics calculator) 110 shown in Fig. 2 differs from that of the first to the third embodiments, as will be discussed later.

Further, in the present embodiment, a part of the

processing technique of a hierarchical compliance operation determiner 114 differs from the one explained in the first to the third embodiments described above. Fig. 62 shows the functional construction of the hierarchical compliance operation determiner 114 of the present embodiment. In the processing of this functional construction, major aspects that are different from the first to the third embodiments will be explained. A compensating total floor reaction force moment distributor 114a determines and outputs not only the node compensating floor reaction force moments of the intermediate nodes and the root node, but also a node compensating floor reaction force moment Mn_dmd of an n -th node ($n=1,2,5,6$) of the leaf nodes, that is, the required floor reaction force moment (the required moment for restoring the posture) about a desired n -th ground contact portion floor reaction force central point ($n=1,2,5,6$). This is because, in the robot 51, moments can be generated about the desired floor reaction force central points of the feet 58 and the hands 62 as the ground contact portions. The technique for determining the node compensating floor reaction force moment Mn_dmd , including the required moments, may be the same technique explained in the first and the second embodiments described above. Further, in the present embodiment, the compensating total floor reaction force moment distributor 114a determines and outputs a corrected desired n -th ground contact portion floor reaction force

moment $Mn_refmdfd(n=1,2,5,6)$ about a desired n-th ground
contact portion floor reaction force central point
($n=1,2,5,6$), which is corrected by generating a node
compensating floor reaction force moment about the desired
5 floor reaction force central point of each corresponding
node, together with a translational force component
 $Fn_refmdfd(n=1,2,3,4,5,6)$ of a corrected desired ground
contact portion floor reaction force. These are used by a
deformation compensation amount calculator 114n to
10 calculate a deformation compensation amount.

A compensating angle determiner (the part enclosed
by the virtual line in Fig. 62) in the present embodiment
determines and outputs not only the compensating angles of
the intermediate nodes and the root node but also the node
15 compensating angle θ_n of an n-th node ($n=1,2,5,6$) among
the leaf nodes. A θ_n determiner that determines these n-
th node compensating angles $\theta_n(n=1,2,5,6)$ determines an n-
th node compensating angle $\theta_n(n=1,2,5,6)$ by the same
processing as that of the foot compensating angle
20 determiner disclosed in Japanese Unexamined Patent
Application Publication No. H10-277969. Incidentally, the
technique for determining the compensating angles
 $\theta_n(n=12,34,56,1234,123456)$ of the intermediate nodes and
the root node other than the above nodes may be the same
25 as the technique explained in the first and the second
embodiments described above.

Further, a corrected desired ground contact portion

position/posture calculator 114g in the present embodiment combines node rotational manipulations on the basis of each n-th node compensating angle

θ_n ($n=1,2,3,4,5,6$) by the technique explained in the first and the second embodiments describe above so as to correct a desired ground contact portion position, and it further corrects the desired posture of an n-th ground contact portion ($n=1,2,3,4,5,6$), thereby determining the corrected desired ground contact portion position/posture of each ground contact portion.

Further, according to the present embodiment, a floor configuration estimator 130 determines an estimated n-th floor height error Z_{fn_estm} ($n=1,2,3,4,5,6$) by the same technique as the technique explained in the aforesaid third embodiment and also estimates a ground contact portion floor inclination error of an n-th ground contact portion θ_{fn} ($n=1,2,3,4,5,6$). The estimation of the ground contact portion floor inclination error θ_{fn} is performed by the same processing as the processing for estimating foot floor inclinations by the floor configuration estimator disclosed in Japanese Unexamined Patent Application Publication No. H10-277969.

The processing techniques of the functional construction of the hierarchical compliance operation determiner 114 of the present embodiment other than the ones described above are the same as that in the third embodiment.

Except for the difference aspects explained above, the arithmetic processing of the control device 50 in the present embodiment is the same as that in the first to the third embodiments.

5 Next, the processing of the aforesaid robot geometric model 110 in the present embodiment will be explained in detail.

10 In the robot 51 of the present embodiment, the number of the degrees of freedom of the joints from the body 53 to the knees is limited to three (only 3 degrees of freedom in the hip joints 55); therefore, it is impossible to change only the difference in height between the right and left knees while strictly maintaining body position/posture, foot position/posture, the horizontal positions of the right and left knees, and the sum of the heights of the right and left knees at their desired values. In other words, if an attempt is made to forcibly change only the height difference between the right and left knees, then twist or slippage would inconveniently take place between ground contact portions (namely, the knees and the feet) and a floor.

25 Similarly, it is impossible to change only the difference in height between the right and left feet while strictly maintaining the body position/posture, the positions of both knees, the horizontal positions of both feet, and the sum of the heights of the right and left feet at their desired values. In other words, if an

attempt is made to forcibly change only the height
difference between the right and left feet, then twist or
slippage would inconveniently take place between ground
contact portions (namely, the knees and the feet) and a
5 floor.

Similarly, it is impossible to change only the sum
of the heights of the right and left knees while strictly
maintaining the body position/posture, foot
positions/postures, the horizontal positions of the right
10 and left knees, and the height difference between the
right and left knees at their desired values. In other
words, if an attempt is made to forcibly change only the
sum of the heights of the right and left knees, then the
body position would be dislocated from a desired position
15 even though twist or slippage may not take place between
ground contact portions (namely, the knees and the feet)
and a floor. As a result, the position of the total
center-of-gravity of the robot 51 and an inertial force
will deviate from desired values, leading to deteriorated
20 stability of the robot 51.

This means that, in any case, the corrected desired
ground contact portion position/posture with deformation
compensation and desired body position/posture that have
been determined by the hierarchical compliance operation
25 determiner 114 cannot be strictly satisfied at the same
time, so that twist or slippage takes place between the
feet 58 or the knees of the robot 51 and the floor or the

total center-of-gravity of the robot 51 and an inertial force deviate from their desired values, possibly resulting in deterioration of the stability of the robot 51 when the robot 51 is in the posture state shown in Fig. 58 and Fig. 59. Incidentally, the hands 62 among the ground contact portions have a degree of freedom of 6 degrees or more of freedom with respect to the body 53; therefore, no twist or slippage will occur between the hands 62 and the floor unless the robot 51 is made to take a posture in which it comes in contact with the floor through portions other than the hands 62 of the arms 54.

Hence, in the present embodiment, the posture or the position/posture of the body 53 are corrected on the basis mainly of a change in the height difference between the right and left knees while restraining, as much as possible, the occurrence of twist or slippage between the knees and the feet 58 among the ground contact portions of the robot 51 and the floor and also restraining, as much as possible, a change in the position of the center-of-gravity (especially the horizontal position) of the body 53.

Figs. 63(a) and (b) show examples of the operations for correcting the posture of the body 53. Fig. 63(c) will be discussed later. These Figs. 63(a), (b), and (c) omit showing the arms 54 and the head 63.

One of the operations for correcting the posture of the body 53 is the operation in which, from the state

wherein the robot 51 is on its knees as shown in Fig.

63(a), the body 53 is rotated (rotated as indicated by an arrow y1) by using, as the axis of rotation, the trunk axis passing approximately the center-of-gravity G of the body 53, as shown in Fig. 63(b), on the basis of a change in the height difference between the right and left knees caused by compliance control.

Further, in the posture in which the robot 51 is on its knees, as shown in Fig. 63, a change in the height difference between the right and left feet 58 and 58 causes the height difference between the right and left knees to change by about half the change in the height difference between the right and left feet 58 and 58.

Hence, the same operation as that of correcting the posture of the body 53 on the basis of a change in the height difference between the right and left knees is performed by only a half amount, as compared with the case of a change in the height difference between the right and left feet, on the basis of a change in the height difference between the right and left feet 58 and 58 caused by the compliance control.

Further, when correcting the posture of the body 53 as described above, the position and the posture of the body 53 are corrected on the basis of a change in the sum of the heights of the right and left knees caused by the compliance control while restraining the occurrence of twist or slippage between ground contact portions (the

knees and the feet 58) and the floor as much as possible, and also restraining, as much as possible, a change in the position (especially the horizontal position) of the center-of-gravity G of the body 53 or in the inclination of a segment connecting the center-of-gravity G and a total floor reaction force central point.

Fig. 64 visually shows an operation for correcting the position and the posture of the body 53 on the basis of changes in the sum of the heights of the right and left knees. Specifically, from the posture of the robot 51 indicated by the dashed lines, as both knees are operated to move down by the compliance control to the posture of the robot 51 indicated by the solid lines, the bottom end portion (or the waist) of the body 53 is shifted forward, as indicated by an arrow y3, and the inclination of the body 53 is shifted backward (in the direction in which the body 53 rises), as indicated by an arrow y2. In other words, the body 53 is tilted backward while maintaining the position of the center-of-gravity G of the body 53 (or the position of a predetermined representative point of the body 53), especially the horizontal position thereof. Alternatively, the body 53 is tilted backward while maintaining the inclination of the segment connecting the center-of-gravity G and the desired total floor reaction force central point P. Further, as an operation for raising both knees is performed by the compliance control, the bottom end portion (or the waist) of the body 53 is

shifted backward, inversely from the above, to shift the inclination of the body toward the front. In other words, the body 53 is tilted forward while maintaining the position of the center-of-gravity G of the body (or the position of the predetermined representative point of the body), especially its horizontal position. Alternatively, the body 53 is tilted backward while maintaining the inclination of the segment connecting the center-of-gravity G and the desired total floor reaction force central point P. Incidentally, Q1" and Q3" in Fig. 64 denote the desired floor reaction force central point of the foot 58 and the desired floor reaction force central point of the knee, respectively, after the position/posture of the body 53 has been corrected as described above. In this example, Q1" is identical to a desired floor reaction force central point Q1 of the foot 58 before the correction.

The above is the overview of the operation for correcting the posture and the position of the body 53.

The processing function of the robot geometric model (inverse kinematics calculator) 110 in the present embodiment is shown by the block diagram of Fig. 65.

In the inverse kinematics calculator 110, first, based on corrected desired n-th ground contact portion position/posture with deformation compensation ($n=1,2,\dots,6$) and the desired ground contact portion positions/postures of the feet 58 and the knees determined

by the gait generating device 100, the correction amount of the height difference between the right and left knees $Z_{kneediffmddf}$ and the correction amount of the sum of the heights of the right and left knees $Z_{kneesummdfd}$ for the desired positions of the right and left knees determined by the gait generating device 100, and the correction amount of the height difference between the right and left feet $Z_{footdiffmddf}$ for the desired positions of the right and left feet determined by the gait generating device 100 are determined.

Specifically, the correction amount of the height difference between the right and left knees $Z_{kneediffmddf}$, the correction amount of the sum of the heights of the right and left knees $Z_{kneesummdfd}$, and the correction amount of the height difference between the right and left feet $Z_{footdiffmddf}$ are determined according to the following expressions 47, 48, and 49.

$Z_{kneediffmddf}$

= Corrected desired fourth ground contact portion position with deformation compensation
- Desired fourth ground contact portion position
- Corrected desired third ground contact portion position with deformation compensation
+ Desired third ground contact portion position

... Expression 47

Zkneesummdfd

= Corrected desired fourth ground contact portion position
with deformation compensation

- Desired fourth ground contact portion position

5 + Corrected desired third ground contact portion position
with deformation compensation

- Desired third ground contact portion position

... Expression 48

10 Zfootdiffmdfd

= Corrected desired second ground contact portion position
with deformation compensation

- Desired second ground contact portion position

- Corrected desired first ground contact portion position

15 with deformation compensation

+ Desired first ground contact portion position

... Expression 49

20 More precisely, "portion position" in expressions 47
to 49 is the height component (the component in the
vertical direction) of the portion position.

Subsequently, the body position/posture correction
amount are determined on the basis of the correction
amount of the height difference between the right and left
25 knees Zkneediffmdfd, the correction amount of the sum of
the heights of the right and left knees Zkneesummdfd, and
the correction amount of the height difference between the

right and left feet $Z_{footdiffmfd}$.

The body position/posture correction amount is composed of a body position correction amount for knee height difference $X_{bkneediffmfd}$, a body posture correction amount for knee height difference $\theta_{bkneediffmfd}$, a body position correction amount for knee height sum $X_{bkneesummfd}$, a body posture correction amount for knee height sum $\theta_{bkneesummfd}$, a body position correction amount for foot height difference $X_{bfootdiffmfd}$, and a body posture correction amount for foot height difference $\theta_{bfootdiffmfd}$. Specifically, these values are determined as follows.

First, based on the correction amount of the height difference between the right and left knees $Z_{kneediffmfd}$, the body position correction amount for knee height difference $X_{bkneediffmfd}$ and the body posture correction amount for knee height difference $\theta_{bkneediffmfd}$ for preventing the correction amount of the height difference between the right and left knees $Z_{kneediffmfd}$ from causing twist or slippage between ground contact portions (the knees and the feet 58) and a floor are determined by geometric calculation on the basis of the correction amount of the height difference between the right and left knees $Z_{kneediffmfd}$ and the desired posture (desired motion) of the robot 51 at that instant (current time).

To be more specific, for example, $X_{bkneediffmfd}$ and $\theta_{bkneediffmfd}$ are determined according to the following

expression 50, where $K_{xkneediff}$ and $K_{thkneediff}$ denote proportional coefficients based on desired postures of the robot 51.

```

5      Xbkneediffmddf = Kxkneediff*Zkneediffmddf
      0bkneediffmddf = Kthkneediff*Zkneediffmddf
... Expression 50

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As an alternative, the relationship between the correction amount of the height difference between the right and left knees (or a 34th node compensating angle θ_{34}) and the correction amounts of the body position/posture may be determined beforehand for some representative desired postures of the robot 51, and it may be stored as a map or function so as to determine $X_{bkneediffmddf}$ and $\theta_{bkneediffmddf}$ on the basis of the map or function and the correction amount of the height difference between the right and left knees $Z_{kneediffmddf}$. Incidentally, in the present embodiment, the body posture is corrected by rotating the body 53 about its trunk axis on the basis of the correction amount of the height difference between the right and left knees, so that the body position correction amount for knee height difference $X_{bkneediffmddf}$ may be zero.

25 Next, in the same manner as described above, based
on the correction amount of the height difference between
the right and left feet 58 and 58 Zfootdiffermdfd, the body

position correction amount for foot height difference
Xbfootdiffmddf and the body posture correction amount for
foot height difference θ bfootdiffmddf for preventing the
correction amount of the height difference between the
5 right and left feet 58 and 58 Zfootdiffmddf from causing
twist or slippage between ground contact portions (the
knees and the feet 58) and a floor are determined by
geometric calculation on the basis of the correction
amount of the height difference between the right and left
10 feet Zfootdiffmddf and the desired posture (desired
motion) of the robot 51 at that instant (current time).

To be more specific, for example, Xbfootdiffmddf and
 θ bfootdiffmddf are determined according to the following
expression 51, where Kxfootdiff and Kthfootdiff denote
15 proportional coefficients based on desired postures of the
robot 51. As described above, the influence of the height
difference of the feet 58 is about half the influence of
the height difference of the knees, so that Kxfootdiff and
Kthfootdiff are one half of Kxkneediff and Kthkneediff.

$$\begin{aligned} Xbfootdiffmddf &= Kxfootdiff * Zfootdiffmddf \\ \theta bfootdiffmddf &= Kthfootdiff * Zfootdiffmddf \end{aligned}$$

... Expression 51

25 Incidentally, in the present embodiment, the body
posture is corrected by rotating the body 53 about its
trunk axis on the basis of the correction amount of the

height difference between the right and left feet 58 and 58, so that the body position correction amount for foot height difference $X_{bfootdiffmddf}$ may be zero.

Subsequently, in the same manner as described above,
5 based on the correction amount of the sum of the heights of the right and left knees $Z_{summddf}$, the body position correction amount for knee height sum $X_{bsummddf}$ and the body posture correction amount for knee height sum $\theta_{bsummddf}$ for preventing the correction amount of the sum
10 of the heights of the right and left knees $Z_{summddf}$ from causing twist or slippage between ground contact portions (the knees and the feet) and a floor are determined by geometric calculation on the basis of the correction amount of the sum of the heights of the right and left
15 knees $Z_{summddf}$ and the desired posture of the robot 51 at that instant (current time).

Alternatively, the relationship between the correction amount of the sum of the heights of the right and left knees and the correction amount of the body
20 posture may be determined beforehand for some representative desired postures, and it may be stored as a map or function so as to determine $X_{bsummddf}$ and $\theta_{bsummddf}$ on the basis of the map or function and the correction amount of the sum of the heights of the right and left
25 knees $Z_{summddf}$.

Alternatively, the correction amounts of body position/posture may be determined as follows. The height

difference between the right and left knees is converted into the 34th node compensating angle θ_{34} that causes the difference, the sum of the heights of the right and left knees is converted into the 1234th node compensating angle θ_{1234} , and the height difference between the right and left feet is converted into the 12th node compensating angle θ_{12} that causes the difference. Then, based on these converted compensating angles, the body position/posture correction amounts may be determined by geometric calculation. Alternatively, the relationship between the converted compensating angles and body position/posture correction amounts may be determined beforehand for some representative desired postures of the robot 51, and it may be stored as a map or function so as to determine body position/posture correction amounts on the basis of the map or function and the converted compensating angles.

Subsequently, the desired body position/posture are moved (rotational movement and parallel movement) by the body position/posture correction amounts to determine desired body position/posture with correction. Specifically, the desired body position/posture are rotationally moved about a trunk axis (or a predetermined axis of rotation (the axis of rotation substantially in a vertical plane)) by the sum of the body posture correction amount for knee height difference and the body posture correction amount for foot height difference

($\theta_{bkneediffmddf} + \theta_{bfootdiffmddf}$), and this is further rotationally moved about a lateral axis by the body posture correction amount for the sum of knee heights $\theta_{bfootsummddf}$, then this is further moved in parallel in the longitudinal direction of the robot 51 by the sum of the body position correction amount for knee height difference, the body position correction amount for the sum of knee heights, and the body position correction amount for foot height difference ($X_{bkneediffmddf} + X_{bkneesummddf} + X_{bfootdiffmddf}$) thereby to determine desired body position/posture with twist correction.

Subsequently, based on the desired body position/posture with twist correction and desired n-th ground contact portion position/posture with deformation compensation ($n=1,2,\dots,6$), a joint displacement command of the robot 51 is determined.

Thus, the processing of the inverse kinematics calculator 110 is carried out as described above.

In other words, according to the sixth embodiment, if the degree of freedom is geometrically insufficient for the operation of correcting the ground contact portion positions/postures of the robot 51, then the hierarchical compliance operation corrects not only the desired ground contact portion positions/postures but also the desired body positions/postures such that a point of the body position (the representative point of the body) or the point (e.g., the overall center-of-gravity) of the

weighted average position of a plurality of portions,
including the body (the weight in this case is desirably
the mass ratio of each portion), especially the horizontal
position of the point is maintained, or the angle of a
5 line that connects the point and a desired total floor
reaction force central point (desired ZMP) is maintained
at the angle in a desired gait.

Further, in other words, the sixth embodiment is
provide with a means that gives priority to the
10 controllability of an actual floor reaction force moment
generated about a desired total floor reaction force
central point (desired ZMP) and determines at least one of
a compensating height and a compensating angle as the
manipulated variable of the relative height or the
15 inclination angle of a predetermined ground contact
portion A (a knee in this case) or the manipulated
variable of the relative height or the inclination angle
of a node having a predetermined ground contact portion A
as a descendant node in order to enhance the stability of
20 the entire posture control of the robot 51, a means for
determining the correction amount of at least one of the
posture and the position of the body while maintaining the
position of the body or the aforesaid weighted average
position of a plurality of portions, including the body,
25 at approximately the position in a desired gait on the
basis of at least one of the aforesaid compensating height
and compensating angle, and an inverse kinematics

calculating means for determining a joint displacement on the basis of at least one of the position and the posture of a predetermined ground contact portion B (foot in this case) except for the aforesaid predetermined ground

5 contact portion A and the body position/posture corrected by the aforesaid correction amount.

Incidentally, in the sixth embodiment, instead of rotating a body posture about the trunk axis of the body 53 of the robot 51, the body 53 may be rotated using the
10 vertical axis as the axis of rotation and using the waist (the bottom end portion of the body 53) of the robot 51 as the center, as shown in Fig. 64(c). In this case, however, the deviation of the center-of-gravity G of the body 53 in the lateral direction would increase. Alternatively, the
15 body posture may be rotated using an axis located midway between the trunk axis of the body 53 and the vertical axis as the axis of rotation. Alternatively, the position and the posture of the body 53 may be simultaneously corrected on the basis of the correction amount of the
20 height difference between both knees or the correction amount of the height difference between both feet 58 and 58. Further, instead of maintaining the position of the center-of-gravity G of the body 53 unchanged, the
position/posture of the body 53 may be corrected such that
25 the overall center-of-gravity position of the robot 51 or the position of the representative point of the body 53 remain unchanged.

In any case, if the degree of freedom is geometrically insufficient in the operation for correcting the position/posture of a ground contact portion of the robot 51 by the compliance operation or the like, at least one of the position and the posture of the body 53 may be corrected from the position/posture of a desired gait so as to restrain the occurrence of slippage, such as twist, of a ground contact portion. Further, instead of correcting at least one of the position and the posture of the body 53, at least one of the position and the posture of a predetermined portion other than the body 53 may be corrected.

[Seventh Embodiment]

An explanation will now be given about a control device for a mobile robot according to a seventh embodiment of the present invention.

In the sixth embodiment, the position/posture of the body has been corrected in order to prevent slippage, such as twist, of a ground contact portion and to minimize the deviations of the position of the overall center-of-gravity of the robot 51 and an inertial force. In the present embodiment (the seventh embodiment), slippage, such as twist, of a ground contact portion has been allowed to a certain extent, and a joint displacement (the displacement between a hip joint 55 and a knee joint 56) or the position/posture of a ground contact portion have

been preferentially corrected so as to restrain the deviations of the position of the overall center-of-gravity of the robot 51 and an inertial force.

More specifically, in the present embodiment, an
5 inverse kinematics calculator 110 carries out the processing shown by the block diagram of Fig. 66 in place of the processing of Fig. 65 explained in the sixth embodiment. Except for this difference, the present embodiment is the same as the sixth embodiment.

10 The inverse kinematics calculator 110 of the present embodiment will be explained with reference to Fig. 66. First, based on corrected desired n-th ground contact portion position/posture with deformation compensation ($n=1,2,\dots,6$) (specifically, the position out of the
15 position/posture) and desired n-th ground contact portion position/posture ($n=1,2,\dots,6$) (specifically, the position out of the position/posture), a correction amount of the height difference between the right and left knees $Z_{kneediffmddf}$, a correction amount of the sum of the
20 heights of the right and left knees $Z_{kneesummdfd}$, and a correction amount of the height difference between the right and left feet $Z_{footdiffmddf}$ are determined according to the aforesaid expression 47, expression 48, and expression 49, and further, the height difference between
25 the right and left knees is converted into a 34th node compensating angle θ_{34} that causes the difference. Similarly, the sum of the heights of the right and left

knees is converted into a 1234th node compensating angle θ_{1234} that causes the sum, and the height difference between the right and left feet is converted into a 12th node compensating angle θ_{12} that causes the difference.

5 Next, based on the converted node compensating angles, joint displacement correction amounts are determined. This is performed as follows. First, a case is assumed where a joint displacement is corrected while fixing the body position/posture of a desired gait and
10 retaining the angle of a segment that connects a desired total floor reaction force central point (a desired 123456th node floor reaction force central point (point P in Fig. 61)) and the overall center-of-gravity of the robot 51 (or the center-of-gravity of the body or the
15 center-of-gravity of a plurality of portions, including the body 53) unchanged. In this case, a j-th joint displacement correction amount ($j=1,2,\dots,\text{total number of joints}$) for the inclination angle (compensating angle) of an n-th node ($n=12,34,1234$) corresponding to each of
20 ground contact portions (a knee and foot 58) to become a unit perturbation amount is determined, and this is defined as a sensitivity Ln_j of the j-th joint displacement relative to the n-th node compensating angle.

 More generally, the j-th joint displacement
25 correction amount ($j=1,2,\dots,\text{total number of joints}$) for the relative angle between the segment connecting a desired total floor reaction force central point (a

desired 123456th node floor reaction force central point)
and an overall center-of-gravity of the robot 51 (or the
center-of-gravity of the body or the center-of-gravity of
a plurality of portions, including the body 53) and the
5 inclination angle of an n-th node ($n=12, 34, 1234$)
corresponding to each of ground contact portions (a knee
and the foot 58) to become a unit perturbation amount is
determined when a joint displacement of a desired gait has
been corrected, and this is defined as a sensitivity Ln_j
10 of the j-th joint displacement relative to the n-th node
compensating angle.

Specifically, if Ln_knee_r denotes the sensitivity
of a right knee joint displacement relative to an n-th
node compensating angle ($n=12, 34, 1234$), Ln_knee_l denotes
15 the sensitivity of a left knee joint displacement relative
to the n-th node compensating angle, Ln_hip_r denotes the
sensitivity of a right hip pitch joint displacement
relative to the n-th node compensating angle, and Ln_hip_l
denotes the sensitivity of a left hip pitch joint
20 displacement relative to the n-th node compensating angle,
then each sensitivity is set according to the following
expression 52 in the posture of the robot 51 on its knees
shown in Fig. 58 and Fig. 59.

25 $L1234_hip_r=0, \quad L1234_hip_l=0, \quad L1234_knee_r=1,$
 $L1234_knee_l=1, \quad L12_hip_r=0, \quad L12_hip_l=0$
 $L12_knee_r=a12, \quad L12_knee_l=-a12, \quad L34_hip_r=a34$

L34_hip_l=-a34, L34_knee_r=0, L34_knee_l=0
... Expression 52

where a12 and a34 denote predetermined constants.

Subsequently, joint displacement correction amounts
5 are determined according to expressions 53 to 56 given
below, where θ_{knee_r} denotes a right knee joint
displacement correction amount, θ_{knee_l} denotes a left
knee joint displacement correction amount, θ_{hip_r} denotes
a right hip joint displacement correction amount (more
10 specifically, the joint displacement correction amount in
the pitch direction of the right hip joint), and θ_{hip_l}
denotes a left hip joint displacement correction amount
(more specifically, the joint displacement correction
amount in the pitch direction of the right hip joint).

15
$$\theta_{knee_r} = L1234_knee_r * \theta1234 + L12_knee_r * \theta12$$
$$+ L34_knee_r * \theta34$$
... Expression 53

$$\theta_{knee_l} = L1234_knee_l * \theta1234 + L12_knee_l * \theta12$$
$$+ L34_knee_l * \theta34$$
... Expression 54

$$\theta_{hip_r} = L1234_hip_r * \theta1234 + L12_hip_r * \theta12$$
$$+ L34_hip_r * \theta34$$
... Expression 55

25
$$\theta_{hip_l} = L1234_hip_l * \theta1234 + L12_hip_l * \theta12$$
$$+ L34_hip_l * \theta34$$
... Expression 56

Other joint displacement correction amounts are determined in the same manner; however, it will be omitted to simplify the explanation.

5 For the 1234th compensating angle θ_{1234} , the displacements (angles) of both knee joints 56 are corrected by the same amount as θ_{1234} , as shown in Fig. 67. Further, for the 12th compensating angle θ_{12} , the displacement (angle) of the right knee joint 56 is
10 corrected in proportion to θ_{12} and also the displacement (angle) of the left knee joint 56 is corrected at the same time by the amount obtained by multiplying the correction amount of the displacement of the right knee joint 56 by -1. In other words, the displacement (angle) of the right
15 knee joint 56 is corrected, as shown in Fig. 67, and the displacement (angle) of the left knee joint 56 is corrected in reverse therefrom. Further, for the 34th compensating angle θ_{34} , the displacement (angle) of the right hip joint 55 in the pitch direction is corrected in
20 proportion to θ_{34} and also the displacement (angle) of the left hip joint 55 in the pitch direction is corrected at the same time by the amount obtained by multiplying the correction amount of the displacement of the right hip joint 55 in the pitch direction by -1. In other words,
25 the displacement (angle) of the right hip joint 55 in the pitch direction is corrected, as shown in Fig. 68, and the displacement (angle) of the left hip joint 55 in the pitch

direction is corrected in reverse therefrom. Incidentally,
Q1 and Q1" in Fig. 67 denote a desired floor reaction
force central point of the foot 58 before the corrections
of the joint displacements described above and a desired
5 floor reaction force central point of the foot 58 after
the corrections, respectively. Further, Q3 and Q3" in Fig.
68 denote a desired floor reaction force central point of
a knee before the corrections of the joint displacements
described above and a desired floor reaction force central
10 point of the knee after the corrections, respectively.

By correcting joint displacements as described above,
the relative angle between the segment connecting a
desired total floor reaction force central point (a
desired 123456th node floor reaction force central point)
15 and the overall center-of-gravity of the robot 51 (or the
center-of-gravity of the body or the center-of-gravity of
a plurality of portions, including the body 53) and the
inclination angle of an n-th node ($n=12,34,1234$)
corresponding to ground contact portions (a knee and the
20 foot 58) is changed by the aforesaid converted node
compensating angle θ_{12} , θ_{23} , and θ_{1234} . Thus, an actual
floor reaction force is faithfully controlled, leading to
improved posture stability and ground contact properties
of the robot 51.

25 Instead of directly correcting joint displacement
commands (desired joint displacements) as described above,
preferentially corrected desired ground contact portion

positions/postures, which are the corrected desired positions/postures of the ground contact portions (specifically, the feet 58 and the hands 62) whose positions/postures are to be preferentially corrected to cause approximately the same desired joint displacements may be determined, and then, based on the determined preferentially corrected desired ground contact portion positions/postures, joint displacement commands may be determined by inverse kinematics calculation.

Because of insufficient degrees of freedom of joints, it is impossible to determine joint displacements by the inverse kinematics calculation to satisfy desired body position/posture and all corrected desired ground contact portion positions/postures; therefore, when carrying out the inverse kinematics calculation, some corrected desired ground contact portion positions/postures out of all corrected desired ground contact portion positions/postures are used. The some corrected desired ground contact portion positions/postures are referred to as the aforesaid preferentially corrected desired ground contact portion positions/postures.

For example, in the situation shown in Fig. 67, for the 1234th node compensating angle θ_{1234} , the position obtained by rotationally moving a desired foot position about a knee may be determined as the preferentially corrected desired foot position.

Incidentally, in the sixth embodiment and the

seventh embodiment, as an example, the compliance operation in the situation wherein the robot 51 is on its knees has been explained. The following will describe the adaptation to a compliance operation in a situation wherein the robot is sitting on a chair. This will be explained as an eighth embodiment.

[Eighth Embodiment]

Fig. 70 shows the construction of an essential section of a robot according to the present embodiment. This robot 71 is provided with floor reaction force sensors 73 and 73 for detecting floor reaction forces (load sensors, such as six-axis force sensors) at the right and left, respectively, of the base end surface of buttocks 72. Instead of providing the floor reaction force sensors 73 and 73 at the right and left, a single floor reaction force sensor that detects the resultant force of the forces applied to the right and left of the base end surface of the buttocks 72 may be provided.

In this case, the outsides of the floor reaction force sensors 73 and 73 are covered with a soft member (elastic member) 74, such as a sponge, as illustrated. To enhance the accuracy of the compliance control in the ground contact portions of the buttocks 72, it is desirable to shape the surface (ground contact surface) of the soft member (elastic member) 74 into a round convex surface in addition to covering them with the soft member.

It is desirable to provide the member 74 such that the horizontal positions of the detection positions of the floor reaction force sensors 73 and 73 (the positions of the sensor main bodies) are aligned with the horizontal position of the apex of the convex surface of the
5 aforesaid member 74 especially when the robot 71 is sitting on a chair through the intermediary of its buttocks 72. This arrangement reduces the nonlinearity of the relationship between a corrective operation of the position/posture of a ground contact portion of the robot
10 71 and a floor reaction force, resulting in better control performance of the compliance control of the robot 71.

In the robot 71, legs (link mechanisms) 52 and 55 are provided extendedly from the right and left sides of the buttocks 72. The structures of the legs 55 and 55,
15 including their joints, are the same as those of, for example, the aforesaid sixth embodiment. Hence, the same reference marks as those related to the legs 5 and 55 in the sixth embodiment will be used, and the explanations thereof will be omitted. However, in the present
20 embodiment, the knees of the legs 55 may not be provided with floor reaction force sensors.

Further, as shown in the figure, a torso (body) 77 is provided on the upper side of the buttocks 72, and arms
25 79 and 79 are provided extendedly from both sides of the upper portion of the torso 77 through the intermediary of shoulder joints 78 and 78. Incidentally, the arms 79 may

have the same structure as that in the robot 51 of the
aforesaid sixth embodiment. Further, the torso 77 is
connected with the buttocks 72 through the intermediary of
a joint 80. In this case, the joint 80 is constructed of
5 a torso turning joint 80a for turning the torso 77 in the
yaw direction relative to the buttocks 72, and a torso
flexing joint 80b for tilting the torso 77 in the
longitudinal and lateral directions relative to the
buttocks 72. The joints provided in the robot 71 as
10 described above are operated by actuators, which are not
shown. Although not shown, a control device 50, which is
similar to that in the aforesaid first embodiment and the
like, is installed in the buttocks 72 or the torso 77.

In the present embodiment, the hierarchical
15 structure may be set, as shown in Fig. 70, for the robot
71 sitting on a chair or the like through the intermediary
of the buttocks 72. More specifically, a right foot 58, a
left foot 58, the right portion of the base end surface of
the buttocks 72 (the portion to which a right floor
20 reaction force sensor 73 is attached), and the left
portion of the base end surface of the buttocks 72 (the
portion to which a left floor reaction force sensor 73 is
attached) as ground contact portions are associated with a
first node, a second node, a third node, and a fourth node,
25 respectively, which are leaf nodes. Further, a 12th node
having the first node and the second node as child nodes
and a 34th node having the third node and a fourth node as

child nodes have been set as intermediate nodes, and a
1234th node having the 12th node and the 34th node as
child nodes has been set as a root node. Further,
according to the policy similar to that in the aforesaid
5 first embodiment and the like, the nodes are associated
with desired floor reaction force central points
 $Q_n (n=1,2,3,4,12,34,1234)$, as illustrated. Incidentally, a
desired floor reaction force central point Q_{1234} of the
1234th node, which is the root node, is identical to a
10 desired total floor reaction force central point P .

In the present embodiment, the control device 50 is
supposed to have a functional construction similar to that
shown in the aforesaid Fig. 2.

In this case, a desired ground contact portion
15 trajectory of a desired motion in a desired gait output by
a gait generating device 100 in the present embodiment is
constructed of the desired position/posture trajectory of
each foot 58 and the desired position/posture trajectory
of the buttocks 72. The body position/posture trajectory
20 of the desired motion means the position/posture
trajectory of the torso 77. Incidentally, the desired
motion includes the position/posture trajectory of the
distal portion of each arm 79. Further, the desired total
floor reaction force central point P is on a virtual plane
25 in the air rather than on an actual floor surface.

In the present embodiment, a hierarchical compliance
operation determiner 114 has the same functional

components as those of the aforesaid sixth embodiment (refer to Fig. 62). However, in the present embodiment, a compensating total floor reaction force moment distributor 114a determines and outputs the node compensating floor reaction force moments of the intermediate nodes and the root node in the hierarchical structure shown in Fig. 70 and the node compensating floor reaction force moments of the leaf nodes corresponding to the feet 58. Further, a compensating angle determiner determines and outputs the node compensating angles of the intermediate nodes and the root node in the hierarchical structure shown in Fig. 70 and the node compensating angles of the leaf nodes corresponding to the feet 58. In this case, the basic techniques for determining these node compensating floor reaction force moments and node compensating angles may be the same as the techniques explained in the first to the third embodiments or the sixth embodiment. Further, a floor configuration estimator determines estimated n-th floor height errors $Z_{fn_estm}(n=1,2,3,4)$ by the same technique as the technique explained in the aforesaid third embodiment, as in the case of the aforesaid sixth embodiment, and also estimates ground contact portion floor inclination errors $\theta_{fn}(n=1,2)$ of the feet 58.

Further, a robot geometric model (inverse kinematics calculator), which is a functional component of the control device 50, corrects the positions/postures of the ground contact portion of the buttocks 72 and the feet 58

(ground contact portions) to restrain the occurrence of slippage, such as twist, of the ground contact portions and also corrects the position/posture of the body (torso) basically on the basis of the corrected desired ground contact portion positions/postures with deformation compensation and the desired body position/posture mentioned above by the same technique as that in the aforesaid sixth embodiment.

The processing of the control device other than that explained above may be the same as that of the aforesaid sixth embodiment.

Several modifications related to the embodiments explained above will now be explained.

An actual node floor reaction force that cannot be directly detected by a floor reaction force sensor may be estimated by an observer by using another actual ground contact portion floor reaction force directly detected by a floor reaction force sensor, a detected value of an acceleration sensor, a detected value of a clinometer, and the like, or it may be estimated by a simplified algebraic relationship. For instance, the hierarchical compliance operation is a rotational compliance operation in which a ground contact portion is rotated about a desired total floor reaction force central point; therefore, even when the compliance operation is performed, the vertical acceleration of the overall center-of-gravity of the robot (or an acceleration component in the direction of a

segment that connects a desired total floor reaction force central point and the overall center-of-gravity)

substantially agrees with the vertical acceleration of the overall center-of-gravity in a desired gait (desired

5 motion) of the robot (or an acceleration component in the direction of a segment that connects a desired total floor reaction force central point and the overall center-of-gravity). Hence, the sum of all actual ground contact portion floor reaction force vertical components

10 substantially agrees with the value obtained by multiplying the sum of the vertical acceleration of the overall center-of-gravity in the desired gait (desired motion) of the robot and the gravitational acceleration by the total mass of the robot.

15 Thus, if an actual n-th node floor reaction force cannot be directly detected, then first, the sum (hereinafter referred to as the actual non-n-th node floor reaction force) of the actual floor reaction forces (actual ground contact portion floor reaction forces) of
20 all leaf nodes that do not have an n-th node as their ancestor node and that are not the n-th node itself is determined.

Next, an estimated n-th node floor reaction force, which is an estimated value of an actual n-th node floor
25 reaction force, is determined according to the following expression 57.

Estimated n-th node floor reaction force

= (Overall center-of-gravity acceleration of desired
gait + Gravitational acceleration) * Total mass
- Actual n-th node floor reaction force ... Expression
57

5

If the body or the like is provided with an
acceleration sensor, then the center-of-gravity
acceleration of the entire robot (hereinafter referred to
as an estimated overall center-of-gravity acceleration)
10 may be estimated on the basis of a detected value of the
acceleration sensor and at least one of a desired gait and
an actual joint displacement, and an estimated n-th node
floor reaction force, which is the estimated value of an
actual n-th node floor reaction force, may be determined
15 according to the following expression 58.

Estimated n-th node floor reaction force
= (Estimated overall center-of-gravity acceleration +
Gravitational acceleration) * Total mass
20 - Actual n-th node floor reaction forces ... Expression
58

For example, in the aforesaid sixth embodiment, if
no floor reaction force sensors for detecting knee floor
25 reaction forces are provided or floor reaction force
sensors for detecting knee floor reaction forces fail,
then an estimated 34th node floor reaction force is

determined according to the following expression 59.

Estimated 34th node floor reaction force
= (Overall center-of-gravity acceleration of desired gait
5 + Center-of-gravity acceleration) * Total mass
- Actual 34th node floor reaction forces
= Overall center-of-gravity acceleration of desired gait *
Total mass
- (Actual 12th node floor reaction force + Actual
10 56th node floor reaction force) ... Expression 59

Further, the estimated 34th node floor reaction
force is used in place of an actual 34th node floor
reaction force to determine the 1234th node compensating
15 angle θ_{1234} by the compliance operation processing, and an
estimated 1234th node relative floor height error
 $Z_{1234rel_estm}$ is also estimated by floor configuration
estimation processing.

In determining the 34th node compensating angle θ_{34} ,
20 it is assumed that the floor is as expected, and an
estimated third node floor reaction force, which is the
estimated value of an actual third node floor reaction
force, and an estimated fourth node floor reaction force,
which is the estimated value of an actual fourth node
25 floor reaction force, are determined on the basis of the
corrected desired third ground contact portion
position/posture with deformation compensation, the

corrected desired fourth ground contact portion position/posture with deformation compensation, and an estimated 34th node floor reaction force.

Further, the estimated third node floor reaction force and the estimated fourth node floor reaction force are used in place of an actual third node floor reaction force and an actual fourth node floor reaction force to determine the 34th node compensating angle θ_{34} by the compliance operation processing.

Instead of determining the corrected desired node floor reaction force moment about a desired node floor reaction force central point on the basis of the required moment for restoring the posture of the robot (compensating total floor reaction force moment) so as to be equivalent to adding the required moment for restoration as described above, a corrected desired node floor reaction force central point obtained by correcting a desired node floor reaction force central point may be determined on the basis of the required moment for restoration (compensating total floor reaction force moment). In this case, a desired node floor reaction force moment about a desired node floor reaction force central point is not corrected, so that it remains to be zero.

Further, in order to compensate for a component that could not be controlled within an n-th node floor reaction force (an expected or detected control error component),

the desired floor reaction force of the parent node of the n-th node may be corrected. More specifically, the value of the difference between an actual n-th node floor reaction force and a desired n-th node floor reaction force in the last control cycle or the value obtained by passing the aforesaid difference through a low-pass filter may be added to the desired floor reaction force of the n-th node.

In the processing of estimating a floor configuration, a tree structure that is different from the tree structure for the compliance control may be set. The tree structure may have two layers composed of a root node and leaf nodes. Further, the weights of nodes may be set to be different from those for the compliance control. A node may be set to any weight as long as the weight of the node is zero in a period during which a node floor reaction force is zero (a period during which all ground contact portions belonging to the node or the ground contact portion corresponding to the node moves in the air).

Further, in the processing of estimating a floor configuration, each corrected node weight may be determined on the basis of the aforesaid corrected desired node floor reaction force central point, and a vector having the determined corrected node weight as an element may be used as the weight for estimating the floor configuration.

When determining an estimated relative floor height error of each point (each ground contact portion) in the processing of estimating a floor configuration, instead of using an actual floor reaction force, a mechanism compliance model, and the detected value of a posture sensor, a deformation amount detector for detecting the deformation amount of a compliance mechanism or the like may be provided so as to use a detected value of the deformation amount detector and a detected value of a posture sensor.

If a floor configuration is to be not only relatively estimated but globally estimated also (estimating a floor configuration on a global coordinate system), then the following may be carried out.

1) Estimating the global height of a floor in a case where the height of the body of a robot on the global coordinate system (hereinafter referred to as the global height) can be detected:

A detector that detects the global height of a predetermined portion, such as a body, of a robot (a body height estimator using an acceleration sensor (e.g., the estimator disclosed in PCT/JP03/05448 by the present applicant) or an external sensor, such as a visual sensor) is used. The value of an estimated floor height error on the global coordinate system is determined on the basis of the estimated body global height, a joint displacement (an

actual joint displacement or a desired joint displacement),
the detected value of an actual body posture inclination,
and the detected value of an actual floor reaction force.
Thus, the estimated floor height error of the root node
5 will have a meaning as the weighted average value of the
global estimated floor height error of every ground
contact portion.

2) Estimating the global height of a floor in a situation
wherein the global height of the body is unknown:

10 If the global value of a certain estimated n-th floor
height error (the error in the global coordinate system
rather than the relative value in a group) is known, then
the global values of the estimated floor height errors of
all points (ground contact portions) are determined on the
15 basis of the above known global value and estimated
relative floor height errors. If the global value of the
estimated n-th floor height error at the start point of a
travel of a robot is known, then the global value of the
floor height error of a ground contact portion that newly
20 comes in contact with the ground will be sequentially
determined as the robot continues to travel; therefore, a
map of floor heights on a travel trajectory of the robot
can be created by storing the above sequentially
determined global values.

25 Further, in the processing of estimating a floor
configuration, each corrected node weight (obtained by
correcting the value of the weight of each node) may be

determined on the basis of the aforesaid corrected desired node floor reaction force central point, and the determined corrected node weight may be used as the weight for defining an actual n-th node relative floor height or the like in estimating the floor configuration. Further, in estimating a floor configuration, the weight used to define the actual n-th node relative floor height or the like does not necessarily have to be the same as the aforesaid weight determined by the desired floor reaction force distributor.

Supplementally, the weight for defining the actual n-th node relative floor height or the like does not necessarily have to agree with the weight determined by the desired floor reaction force distributor; however, if they are to agree with each other (in this case, the desired floor reaction force central point of the root node will automatically agree with a desired total floor reaction force central point), then the influence of a floor configuration error can be canceled simply by adding an n-th node estimated floor inclination error to an n-th node compensating angle ($n=1,2,\dots$) for the compliance operation, thus making it possible to reduce the calculation volume for canceling the influence of the floor configuration error.

Furthermore, estimated floor configuration errors may be stored as the map information of a floor configuration, and a desired gait may be generated on the

basis of the stored map information of the floor configuration when a robot walks in the same place next time.

5 Incidentally, the arithmetic processing sequences in the block diagrams or the flowcharts showing the arithmetic processing functions in the embodiments described above may be subjected to equivalent modifications.

10 Further, the present invention can be applied not only to a mobile robot but also a wheel-type mobile body having an active suspension.

Industrial Applicability

15 As described above, the present invention is useful as the one that makes it possible to provide a mobile body, such as a legged mobile robot, that permits highly stable, smooth operations to be achieved by properly controlling floor reaction forces.